

Tillett and Hague Technology Guidance and Control System

Reference manual for implement manufacturers

Inter-row



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Disclaimer:

Considerable effort has gone into making Tillett and Hague guidance and control systems reliable under normal commercial conditions. However, it is possible that under some adverse circumstances the guidance system will be unable to operate reliably. We recommend that it is made clear to operator's that it is their responsibility to ensure that the machine is operating in a satisfactory manner. Should a fault develop, or excessive crop damage occur, operation should cease, and users should be encouraged to contact their dealer or implement manufacturer for advice.

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1. Introduction to this manual

This manual provides implement manufacturers incorporating Tillet and Hague guidance and control systems into their products with all the technical information they need for installation. It also includes advice on setting up prior to and during initial field running, as well as guidance on using fault finding tools.

There is an Appendix giving additional detailed technical information as well as a section on a demonstration mode that can be useful for marketing and training.

This manual is not intended for use by implement operators. However, Tillet and Hague Technology Ltd do give permission for extracts from this manual to be used by their customers in the production of implement operator manuals.

It is the responsibility of the implement manufacturer to ensure that all implements are sold with the information necessary for safe and effective operation. Tillet and Hague Technology Ltd will on request provide reasonable assistance in the development of operator manuals and other training material.

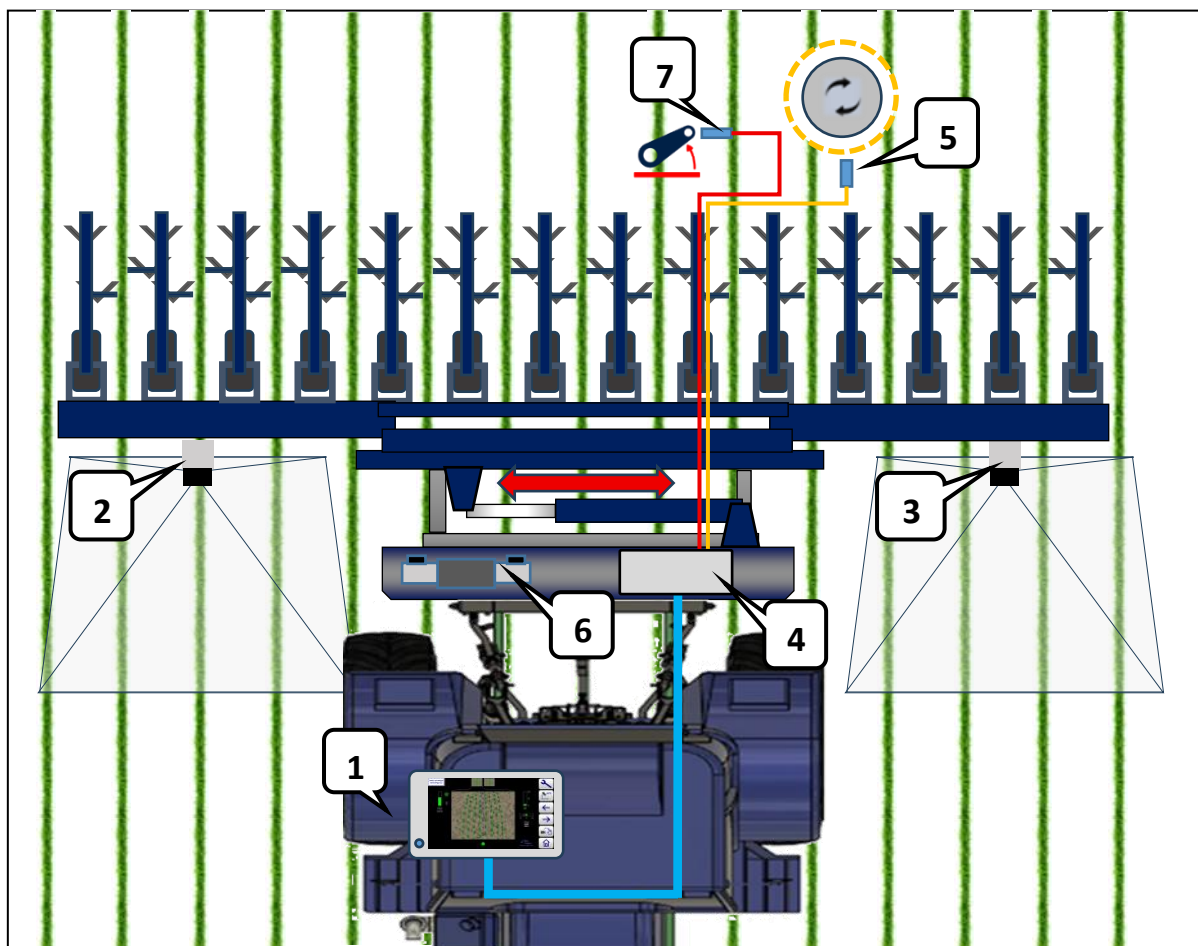
2. Product description

This vision guidance system analyses data from digital cameras to identify crop rows. Rows are tracked over successive images and their position be used to steer an implement relative to those crop rows.

Tillett and Hague's software has been refined over 25 years of commercial use and development and has to date been used to guide over 4000 vision guided implements around the world. The latest version of this software incorporating machine learning techniques runs on a powerful but efficient custom console with a touch screen and bright high contrast display. This provides operators with highly visible user-friendly information including live images with graphical overlay. Using high performance imagers in a robust purpose designed package that is simple and cost effective to install, our system gives world leading row tracking performance.

There are 3 main components to the system.

- A digital camera (2) or cameras (2/3) mounted on the implement looking ahead at a wide area of crop normally taking in several rows each.
- A cab mounted console (1) containing a computer to analyses camera images and find exact row centres.
- An implement mounted control box (4) housing the electronic board that controls hydraulic valves (6) for side shift or disc steering. That board also accepts input from position and proximity sensors (5/7) necessary for closed loop control.

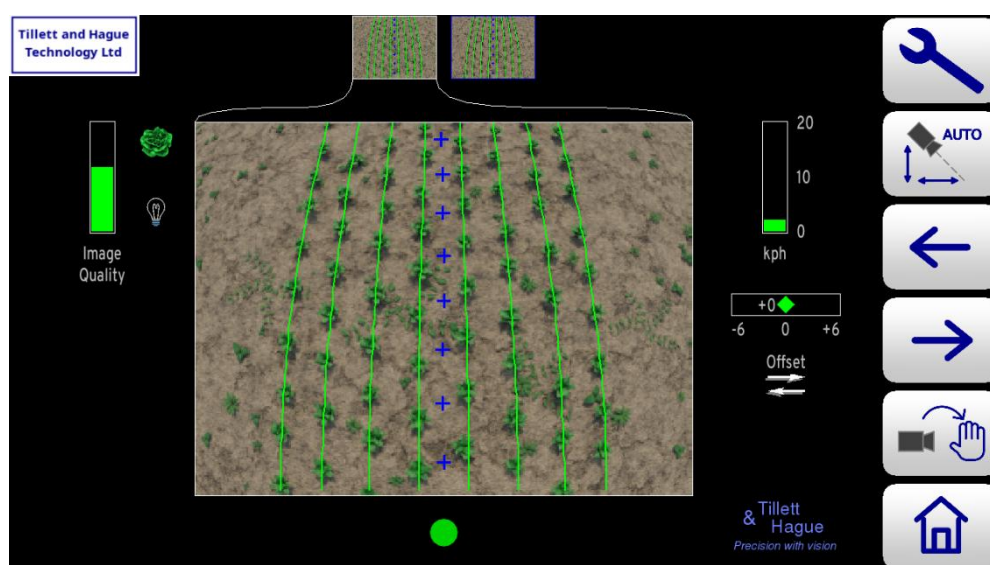


Schematic of a rear mounted inter-row guidance system with side shift (For other implement geometry options including front mounting, disc steering and multi-section see [Tillett and Hague Design Notes](#))

The system uses a colour camera to pick out green crop and weed from backgrounds containing soil, stones and trash. (Systems to work in other crop colours are also available.) Crop rows are located within a scene by matching a template corresponding to the known planting pattern with crop rows as they appear in the camera image. That image is displayed live on the console with the template overlaid as green lines.

Matching a template to a broad area of crop rather than locating individual rows improves reliability especially when parts of those rows are not present or obscured by weeds. Template shape is determined by a configuration pre-programmed to suit a particular planting geometry and implement configuration. Different configurations can be created for different crops and implement geometries.

Live video allows user to check for a good match between template and crop rows, which is important for accurate row following.



Console working screen showing a typical live video image for a 2-camera machine with the template superimposed as green lines over crop rows.

Electrical system

The system is designed to operate from a tractor nominal 12V supply fused at no more than 20A for short circuit protection. The power consumption for electronic parts including the console is only 20W, but solenoid valves driven by the system will increase that substantially when they are activated. The system is tolerant to voltage surges up to 27 V and will continue to operate for short periods down to 6V providing continuity during tractor starts.

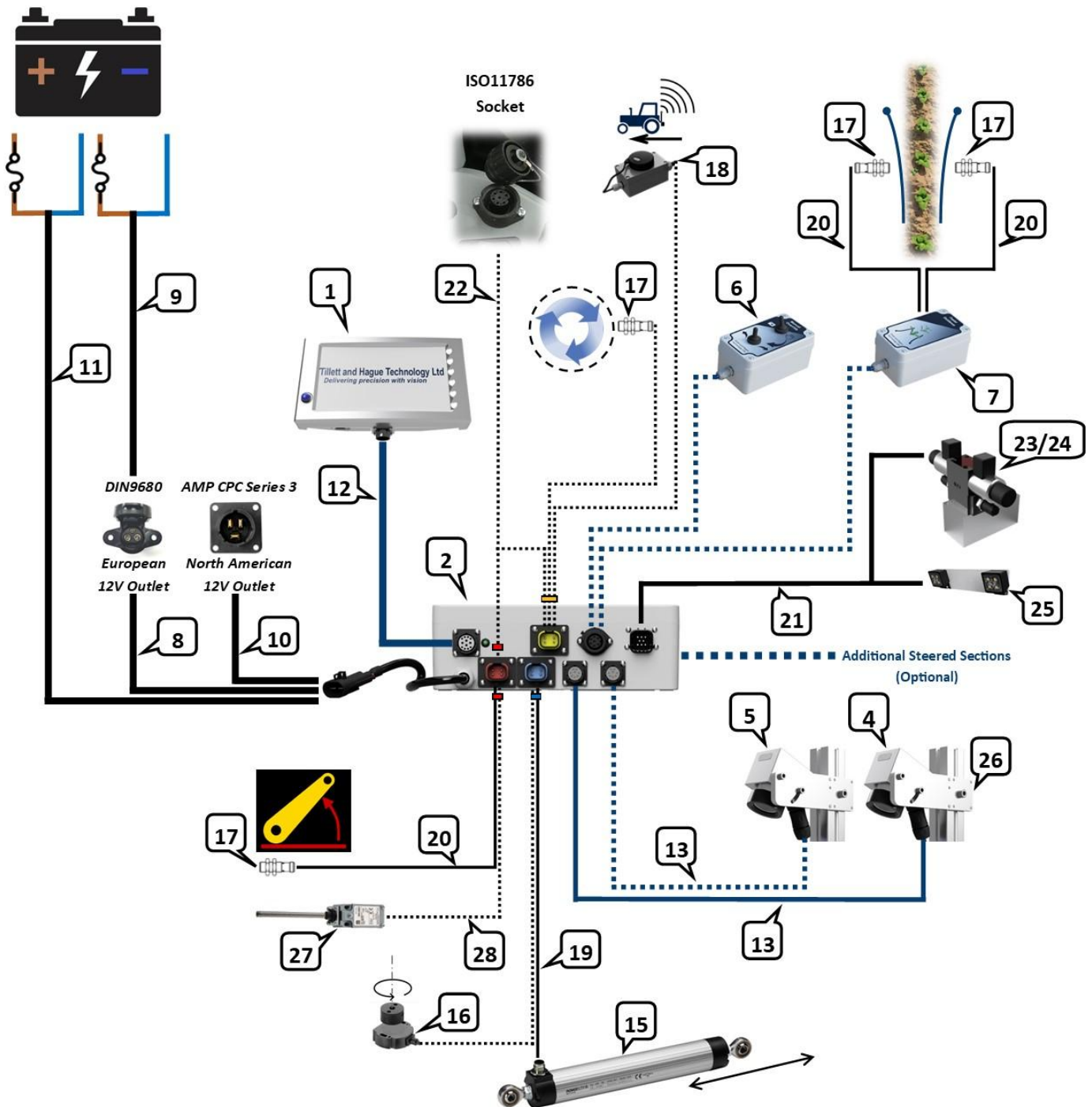
Hydraulic system

The system normally operates 12V solenoid operated 4/3 directional control valves, either proportional or non-proportional, that meter hydraulic oil into cylinders linked to side shift or disc steering mechanisms. It is normal with non-proportional valves for the implements hydraulic circuit to include components that facilitate manual adjustment of the rate of cylinder movement, though it may also be possible to do this via the tractors hydraulic control system. For further discussion of hydraulic systems see the [Annex](#).

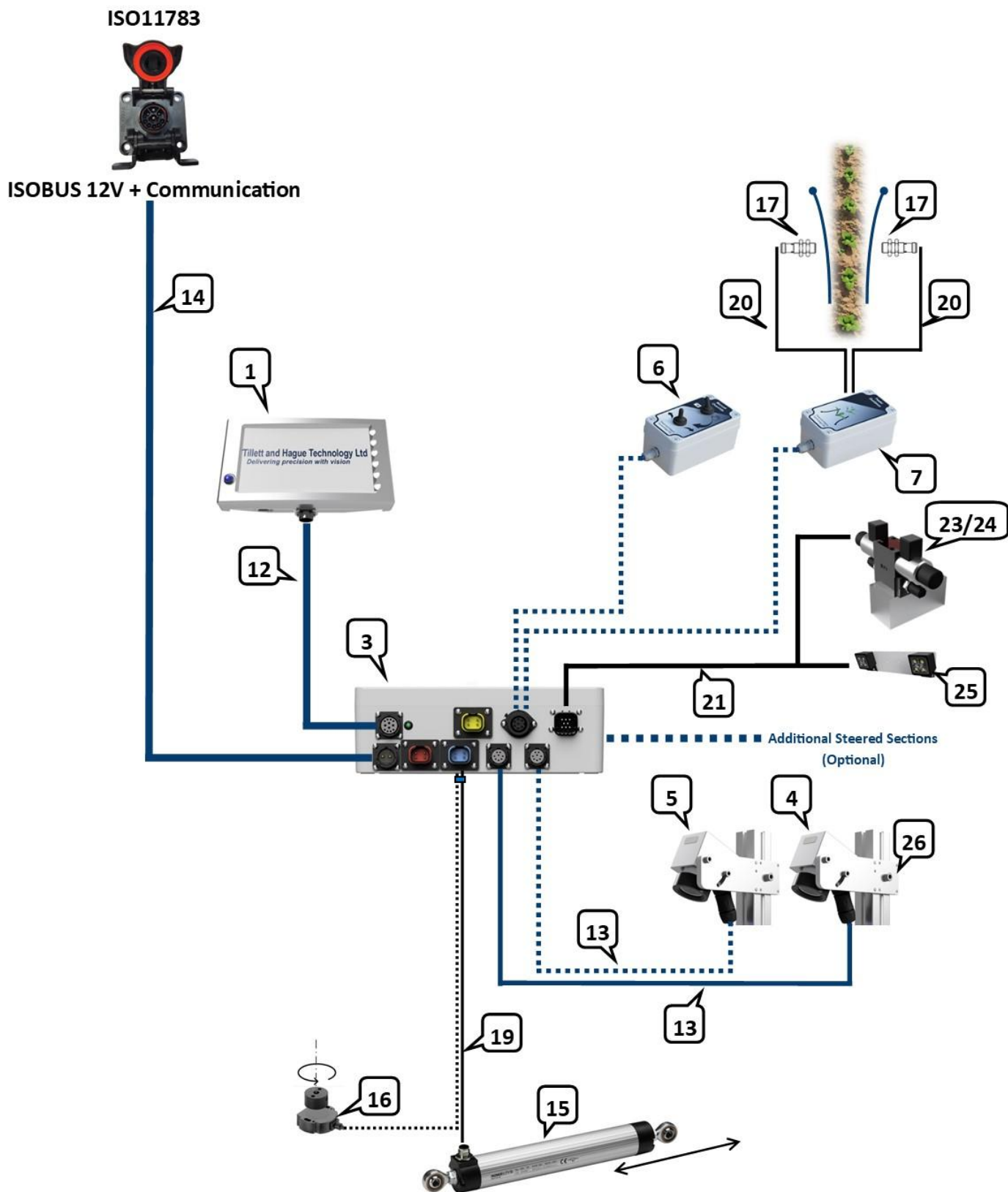
3. System overview

Below we give a control system overview for a standard system with both ISOBUS and non-ISOBUS options. For more wiring detail and a wider range of control system configurations, including multi-section systems tracking multiple independently planted bouts, [Contact THT](#).

Standard system – with optional equipment shown with broken lines

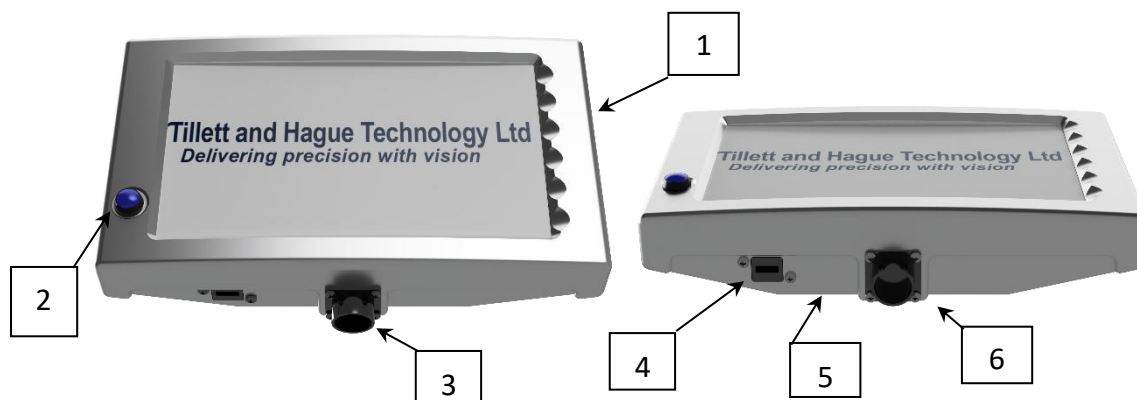


ISOBUS standard system overview - with optional equipment (broken lines)



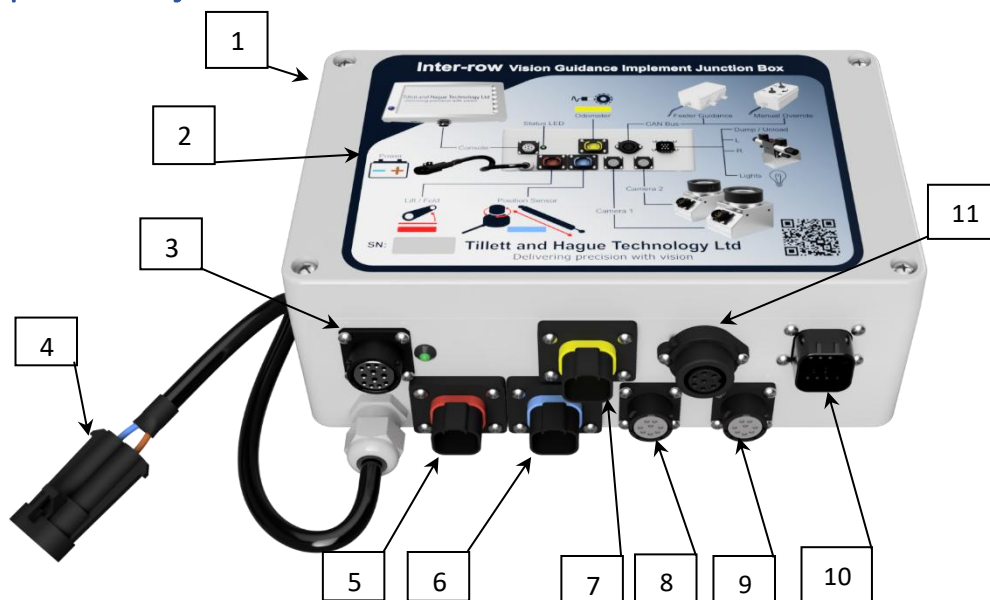
	Part Name	Part number
1	Console/Cab mounted terminal	BOX001
2	Interrow implement control module	BOX002
3	ISOBUS Interrow implement control module	BOX002-ISO
4	Camera 1	BOX003
5	Camera 2 (optional)	BOX003
6	Manual override control box (optional)	BOX004
7	Feeler override system (optional)	BOX005
8	Euro "D" plug power cable	CBL004
9	Euro "D" plug receptacle to battery cable (optional)	CBL007
10	North American power cable	CBL004-USA
11	Direct to battery power cable (optional)	CBL020
12	Console to implement module cable	CBL001
13	Implement module to camera cable	CBL002
14	ISOBUS Implement module to tractor cable	CBL051
15	Linear potentiometer position sensor	SEN002
16	Rotary position sensor useful for disk steering applications (optional)	SEN005
17	Proximity sensor for lift input/optional speed input	SEN001
18	GPS alternative speed sensor (optional)	SEN003
19	Potentiometer sensor cable	CBL003
20	Proximity sensor input cable	CBL005
21	Valve connection loom	CBL006
22	ISO11786 speed and lift input cable (optional)	CBL016
23	Hydraulic control valve block assembly (optional)	HYD001
24	Proportional Hydraulic control valve block assembly with filter (optional)	HYD004
	Condition Monitoring Microcontroller Module	BOX012
25	LED night operation light assembly (optional)	BKT002-2LED
26	Universal camera bracket (optional)	BKT001
27	Snap action limit switch for lift detection (Alternative)	SEN004
28	Snap action lift input cable (Alternative)	CBL021
	Opto-isolated input/output board	PCB008

3.1 Console (cab mounted terminal) PN: BOX001



	Features
1	Cab mounted console.
2	Power button
3	12-way Console cable connection.
4	USB socket (For system updating/backup via USB stick & keyboard connection)
5	VESA mounting holes (100x100mm)
6	RAM mounting plate. (1" ball) Recommended but not supplied

3.2 Implement junction box PN: BOX002



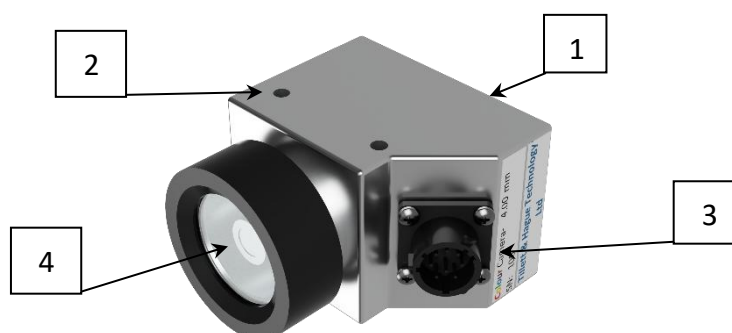
	Features
1	Implement junction box (For I/O Schematics See Annex)
2	Junction box connection label.
3	Main Console cable connector.
4	Power supply cable (12V non-switched should be externally fused to 20 amp)
5	Lift and fold cable connector (Proximity, reed, micro-switch). (Red)
6	Slide/steer position (Potentiometer 3-10 KΩ or Hall effect sensor 12v or 5V) (Blue)
7	Odometer cable connector. (GPS/ Proximity sensor input) (Yellow)
8	Ethernet Camera Connector No: 1
9	Ethernet Camera Connector No: 2
10	Control valve cable connector. (3-amp solenoid control)
11	CAN connector (Manual override pendent/Feeler control box)

3.3 Implement junction box with ISOBUS Tractor Connection PN: BOX002-ISO



	Features
1	Implement junction box (For I/O Schematics See Annex)
2	Junction box connection label.
3	Main Console cable connector.
4	ISOBUS Connection to tractor, 12V and ISOBUS via CBL051
5	Lift and fold cable connector (Proximity, reed, micro-switch). (Red)
6	Slide/steer position (Potentiometer 3-10 KΩ or Hall effect sensor 12v or 5V) (Blue)
7	Odometer cable connector. (GPS/ Proximity sensor input) (Yellow)
8	Ethernet Camera Connector No: 1
9	Ethernet Camera Connector No: 2
10	Control valve cable connector. (3-amp solenoid control)
11	CAN connector (Manual override pendent/Feeler control box)

3.4 Camera (6mm or 4mm lens) PN: BOX003



	Features
1	Ethernet camera
2	2 x M6 mounting threads each side
3	8-way camera cable connection.
4	6mm (narrow angle) lens BOX003-6 and 4mm (wide angle) lens BOX003-4 options

For cameras with NIR sensitivity add **-NIR** to the end of the part number..

Cameras serial number 4470 onwards (September 2022) are a Mk2 version which are mechanically and electrically identical to Mk1. However, Mk2 cameras use different software making it impossible to mix camera types on the same machine. Implement modules serial numbers prior to 2230 (December 2021) contain firmware that is not compatible with Mk2 cameras. Please [contact us](#) for solutions if these limitations are an issue.

3.5 Console cable 6m PN : CBL001-6, CBL018-6, CBL029-6, CBL039-6



	Features
1	12-way console cable [Female-Male] 6m and 10m lengths as standard CBL001-L
2	12-way console extension loom [Male – Female] 6m length as standard CBL018-L
3	12-way console extension loom [Female – Male] 6m length as standard CBL029-L
4	12- way console extension loom inline [Male - Female] 6m length as standard CBL039-L

3.6 Camera cable 5m PN: CBL002-5



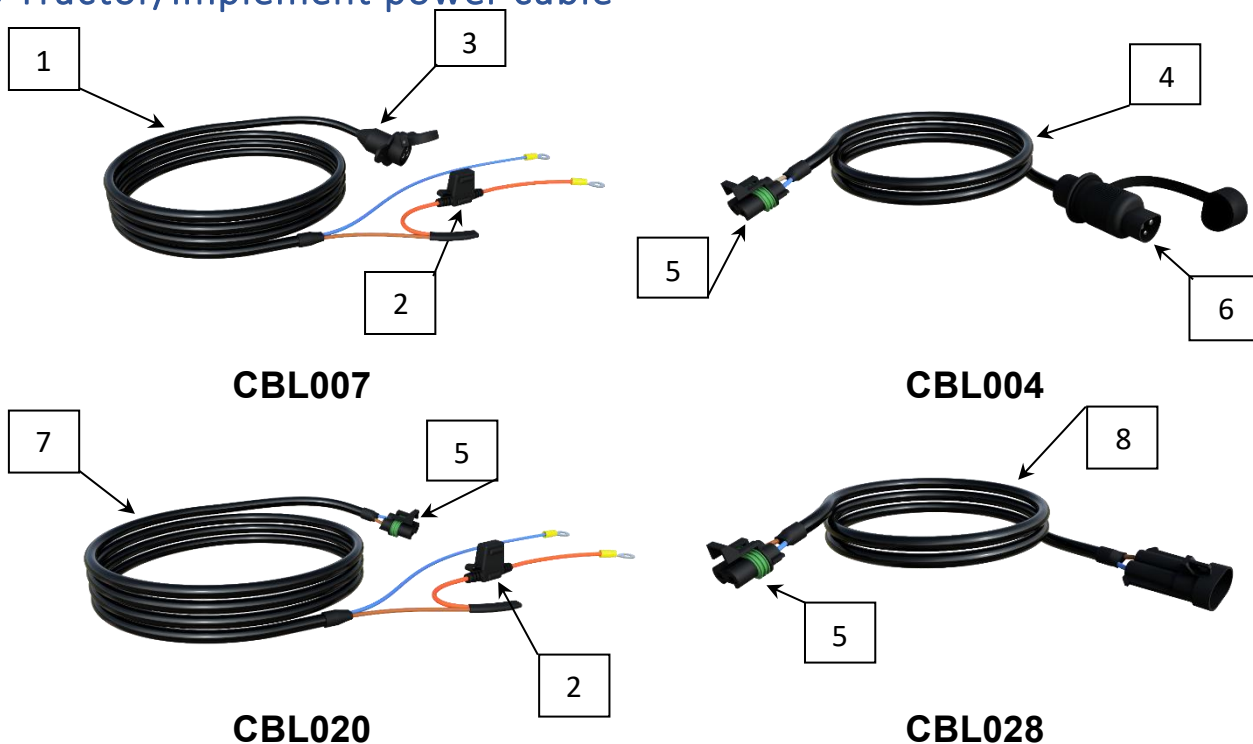
	Features
1	Camera cable, 2m, 5m, 7m and 10m lengths as standard CBL002-L
2	8-way female plug. (To Camera)
3	8-way Male plug. (To Implement junction box)

3.7 Camera disconnect at headstock extension cable PN: CBL013



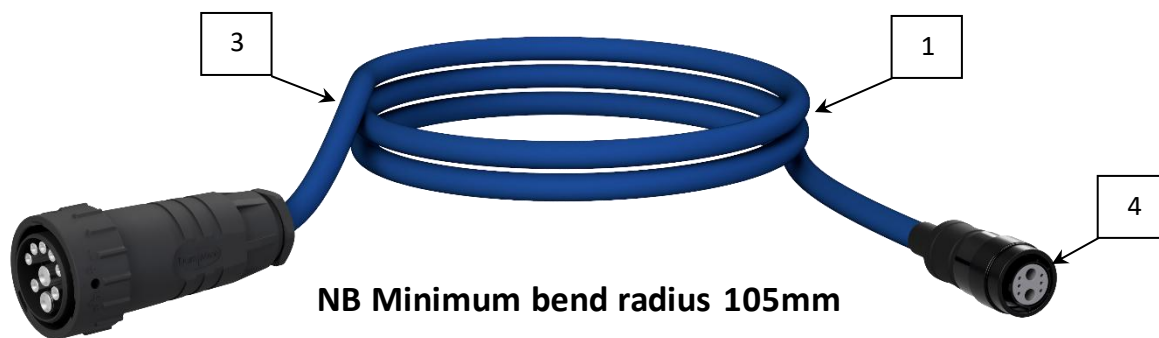
	Features
1	Camera cable, 1.5, 2m lengths available CBL013-L
2	8-way female plug (mounted in box), ideal for quick hitch toolbar
3	8-way Male plug. (To Implement junction box)

3.8 Tractor/implement power cable



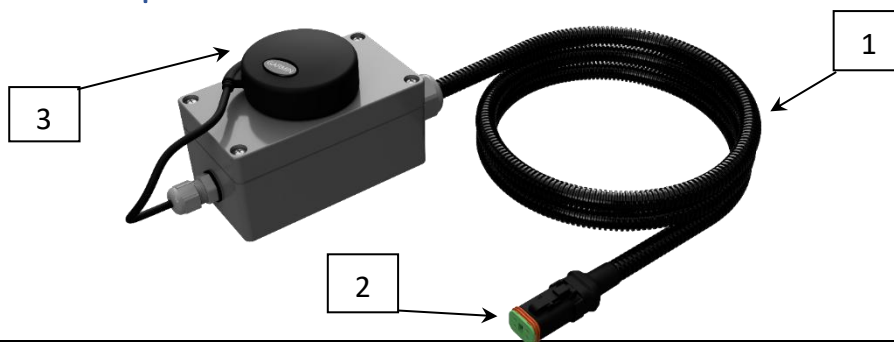
	Features
1	Optional tractor power cable (3 Meters long as standard) CBL007-L
2	Fuse holder (20-amp MAX)
3	3-way Female 'D' plug.
4	Implement junction box power cable (3 Meters long as standard) CBL004-L
5	2-way power connector.
6	3-way Male 'D' plug.
7	Optional direct to battery power cable (5m and 8m variants) CBL020-L
8	Power extension cable CBL028-L

3.9 ISOBUS 12V and Communication cable PN: CBL051-3



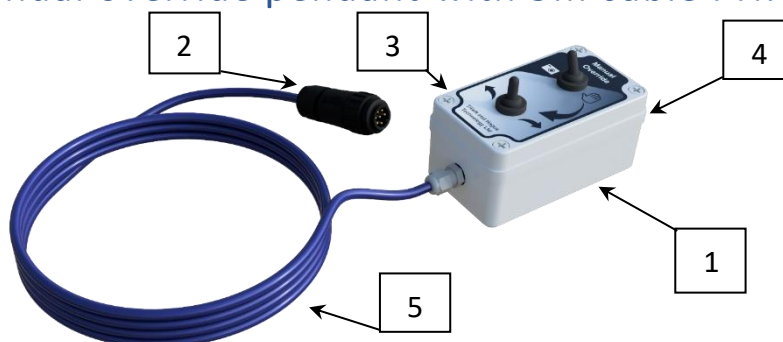
	Features
1	ISOBUS to Implement Module Cable 3m
2	ISOBUS Connector to tractor
3	12V and Communication cable 3m, other cable lengths available on request CBL051-"L"
4	Connector to Implement Module, only compatible with a BOX002-ISO

3.10 Optional GPS speed sensor with 2m cable. PN: SEN003



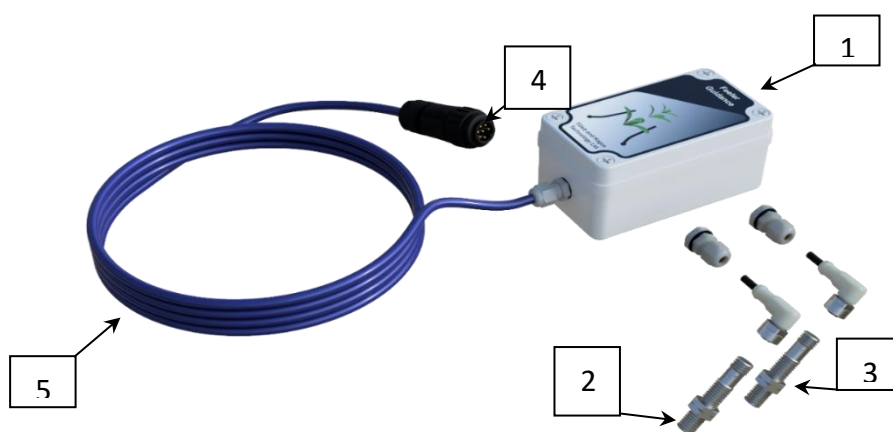
	Features
1	GPS Speed sensor loom.
2	4-way female plug. (To connector No:7 Yellow implement Junction box)
3	GPS module/ antenna.

3.11 Optional Manual override pendant with 5m cable PN: BOX004-5



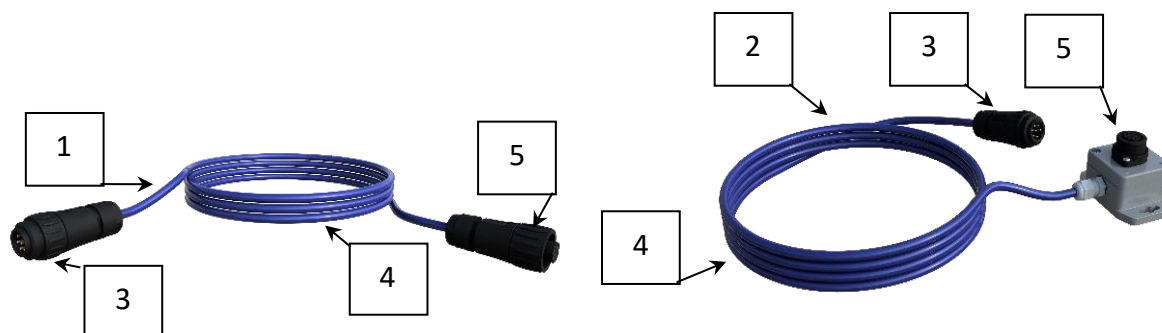
	Features
1	Manual override pendant (For BOX004 schematic Contact THT)
2	6-way Male CAN plug.
3	Manual movement Left-Right Toggle.
4	Manual override/camera guidance toggle switch.
5	5m Integrated CAN lead as standard

3.12 Optional Feeler guidance junction box. PN: BOX005-5



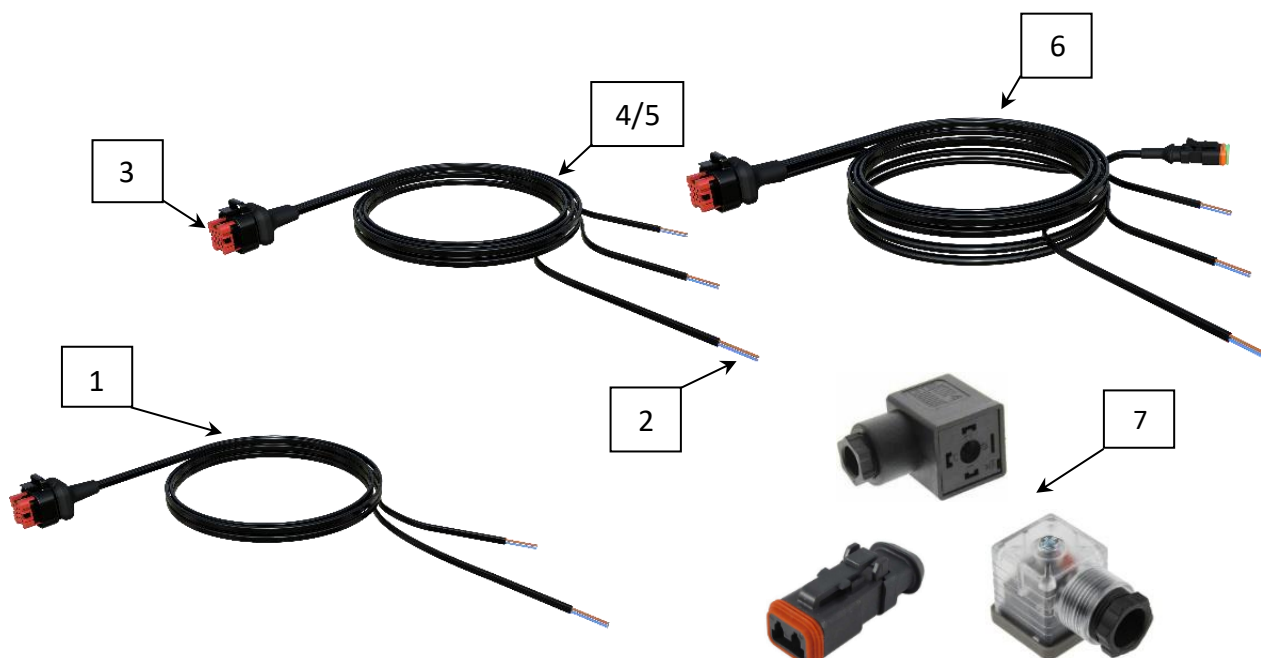
	Features
1	Feeler guidance system (For BOX005 schematic Contact THT)
2	Left Proximity sensor (To sense feeler arm movement)
3	Right Proximity sensor (To sense feeler arm movement)
4	6-way Male CAN plug.
5	5m integrated CAN lead as standard

3.13 CAN Extension loom PN: CBL019-L, CBL033-L



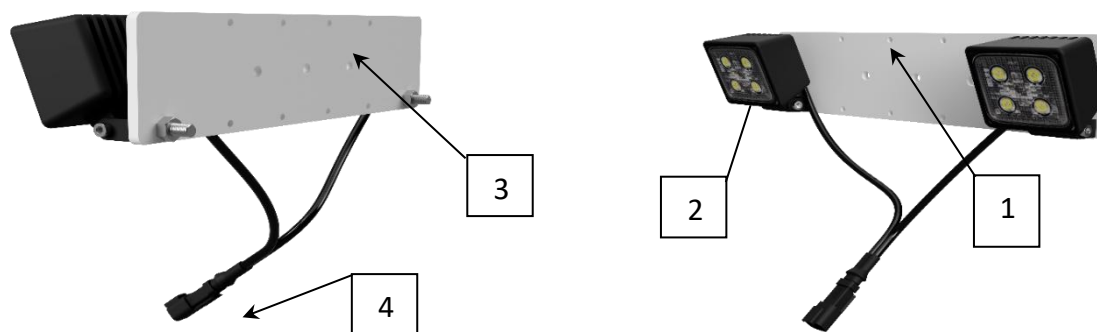
	Features
1	Low power and CAN extension loom inline, CBL019-L
2	Low power and CAN extension loom (panel mounted version), CBL033-L
3	6-way Male CAN plug. (To CAN connector No:11 implement Junction box)
4	CAN and power cable
5	6-way Female CAN plug. (To CAN Device)

3.14 Valve loom 2m. PN: CBL006-2



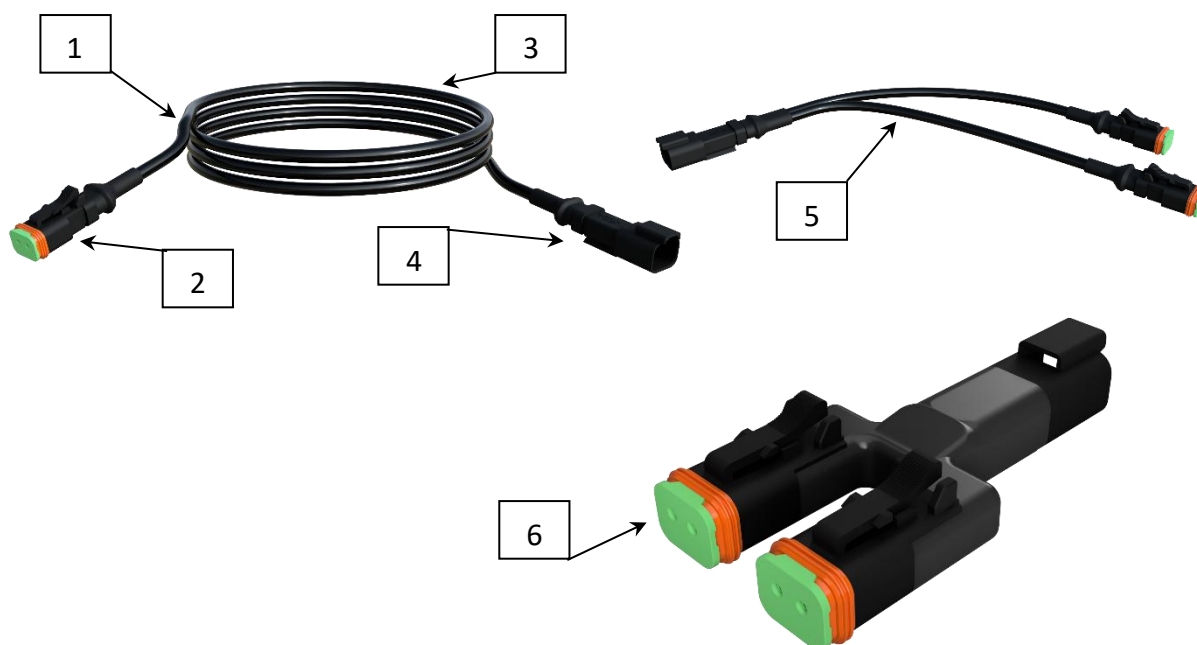
	Features
1	Basic hydraulic solenoid valve loom.
2	2m Open wire tails to take 2-way valve connector plugs.
3	8-way Male plug (To connector NO:10 implement junction box)
4	Basic loom with additional output for hydraulic dump valve CBL006-2-WD-2
5	Basic loom with additional output for night lights CBL006-2-WL-2
6	CBL006-2-WD-2-WL-2-DT integrates both 2m dump valve and 2m night operation lights into valve loom
7	Various connector options available e.g. DIN, Deutsch DT etc. e.g. 2m valve loom with valve DIN connectors and 2m lights cable to DT connector CBL006-2-DIN-WL-2-DT

3.15 Night operation lights and mounting bracket assembly PN: BKT002-2LED



	Features
1	Night operation lights activated by touch screen display
2	x2 12W 1080 Lumen LED worklamps
3	Universal mounting bracket to camera pole
4	2-way Deutsch DT connector

3.16 Night operation light extension and “Y” adaptor cable PN: CBL017-L, CBL027-0.25



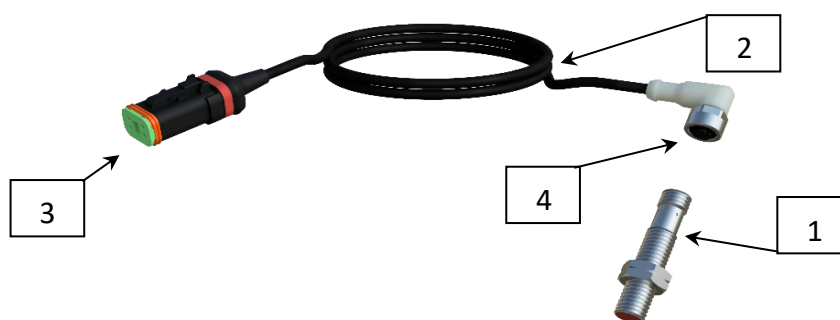
	Features
1	Night operation light extension cable
2	2-way Deutsch DT connector female
3	2 core cable available in various lengths (3m, 4m, 5m, 6m) CBL017-L
4	2-way Deutsch DT connector Male
5	“Y” adaptor cable enabling connection to multiple lights CBL027-0.25
6	“Y” adaptor connector enabling connection to multiple lights CBL027-0

3.17 Potentiometer/position sensor cable 2m PN: CBL003-2 and CBL035-2



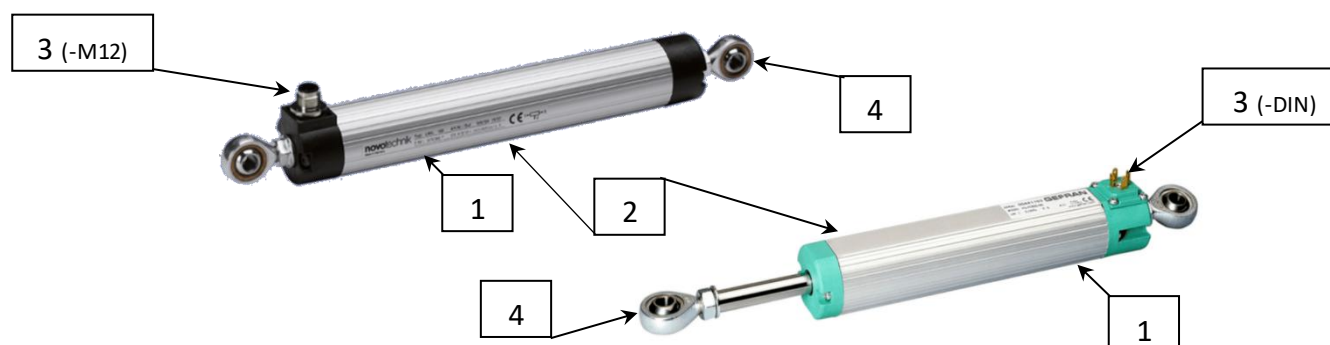
	Features
1	Position or lift/fold sensor cable.
2	4-way Female plug (To connector NO:5 Red (lift/fold), NO:6 Blue (position) implement junction box)
3	3 core open cable CBL003-L (Lift, Steer pot)
4	4 core open cable CBL035-L (Lift + Fold, Steer pot + Lightbar Pot)
5	Various connector options available e.g. DIN, M12, TE3, ferrule etc.

3.18 Proximity sensor and Lift/Speed sensor lead 5m PN: SEN001 & CBL005



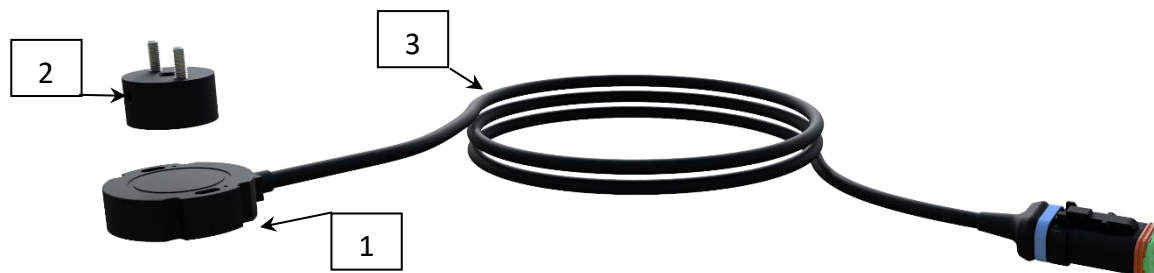
	Features
1	Ferrous metal sensing NPN proximity sensor
2	5m sensor lead
3	4-way Female plug (To connector NO:4/8 implement junction box Red/Yellow)
4	M12 connector to sensor
5	12mm mounting hole for sensor

3.19 Linear potentiometer for machine position PN: SEN002-L



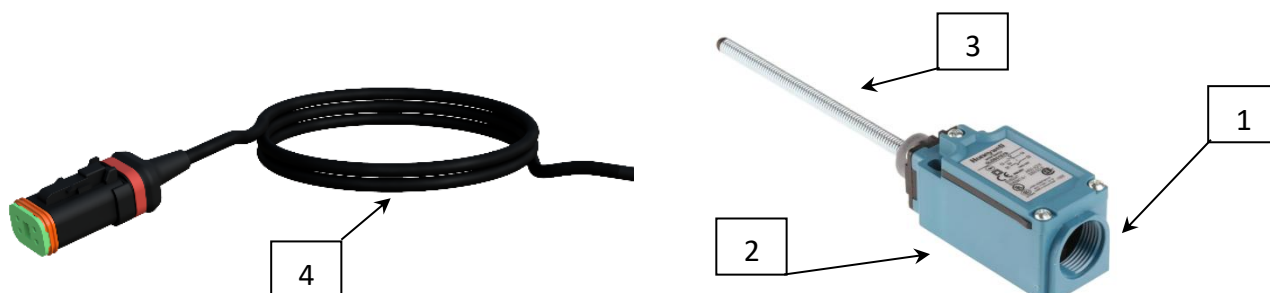
	Features
1	5KΩ Linear potentiometer (Novotechnik or Gefran)
2	We stock strokes of 300mm and 500mm. Other strokes possible
3	Connector to sensor lead (M12 for Novotechnik, DIN for Gefran)
4	8mm mounting points

3.20 non-contact rotary position sensor PN: SEN005-L + SEN005-M



	Features
1	5V non-contact position sensor with cable SEN005-L
2	Position sensor magnet SEN005-M
3	2.5m cable length
4	Can be connected directly to NO: 6 (Blue) using Deutsch DT connector

3.21 Snap action limit switch sensor PN: SEN004



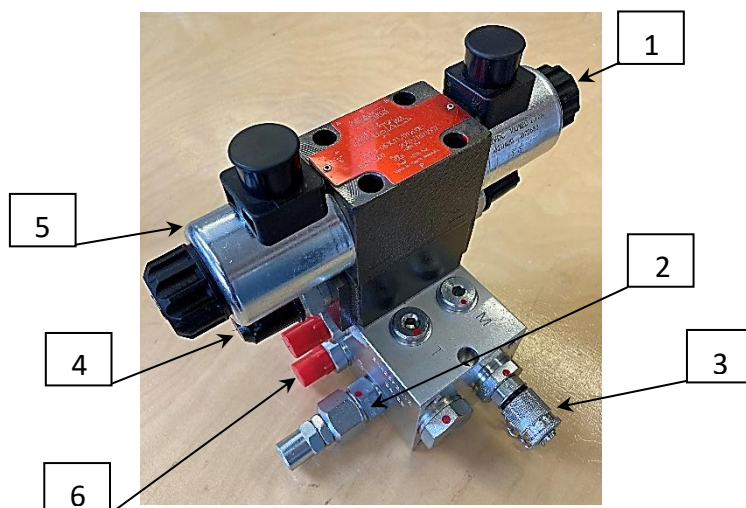
	Features
1	SPST limit switch
2	NO/NC contacts for use as lift or fold input
3	Coil spring actuator for ease of mounting
4	For use with CBL021-L to connect to implement module NO:5 (Red)

3.22 ISO11786 Tractor Lift/Speed input cable PN: CBL016-A



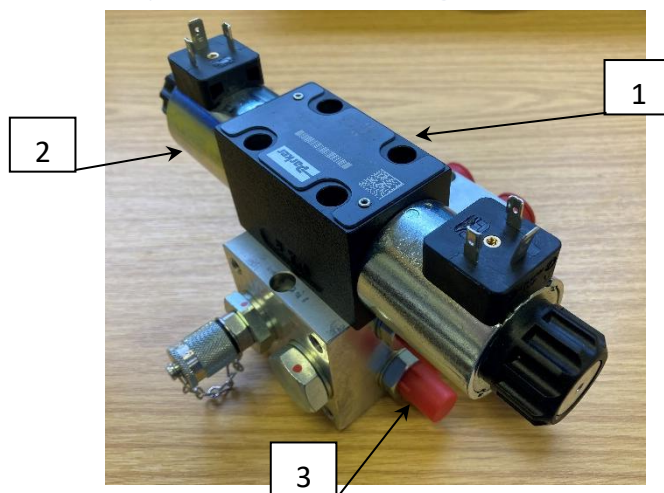
	Features
1	ISO11786 connector for tractor speed/lift connection
2	4m cable length
3	X2 4-way Female plug (To connector NO: 5 (Red) /7 (Yellow) implement junction box)

3.23 Hydraulic steering control valve PN: HYD001



	Features
1	Open centre directional control valve
2	Pressure reducer integrated into manifold block
3	Test point fitting for setting circuit pressure (gauge available HYD003)
4	Flow control for metering steering speed
5	12V solenoid coils
6	BSSP fittings, Hydraulic piping kit available if required PN: HYD002

3.24 Proportional hydraulic steering control valve PN: HYD004



	Features
1	Closed centre proportional directional control valve
2	Proportional solenoid coils
3	BSSP fittings, Hydraulic piping kit available if required PN: HYD002
4	Pressure line filter (not shown)

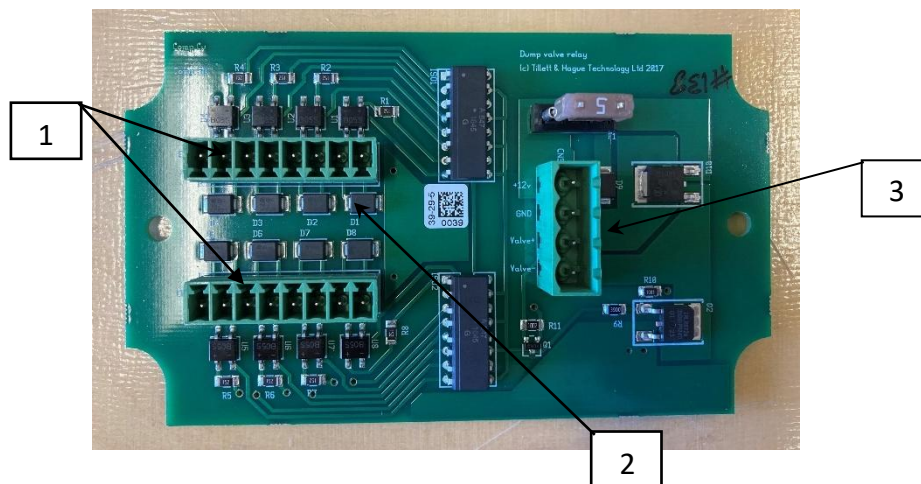
3.25 Condition Monitoring Microcontroller Module PN: BOX012



Can be used with appropriate sensors to monitor hydraulic oil temperatures, pressures and filter blockages with warnings displayed on the console working screen.

	Features
1	Hydraulic and Spray condition monitoring options
2	X2 Hydraulic Pressure, x1 Temperature, x1 Filter blockage inputs (BOX012-H)
3	X3 Spray pressure, x1 Master pressure inputs (BOX012-S)
4	Panel Mount CANbus connector for use with CBL019

3.26 Opto-isolated input/output board PN: PCB008



	Features
1	12 opto-isolated input channels
2	Electrically isolated inputs to trigger a single output
3	12V supply and single valve output channel
4	107mm x 70mm x 20mm board dimensions
5	4mm x 104.5mm mounting holes

4. Safety

1. These guidelines only cover aspects of safety specific to this guidance product. Machines should be operated under general safety and accident prevention regulations.
2. The operator is responsible for safe operation of the machine even when automatic steering is operating.
3. The guidance system is only intended to guide agricultural implements within agricultural fields.
4. When carrying out repairs or adjustments to an implement, ensure that the hydraulic supply is off, and pressure is zero.

Be aware that spurious speed signals can be generated potentially causing the side shift/steering discs to move unexpectedly. This is most likely if odometry is generated via GPS, which is inclined to drift, or via computer vision, particularly if people are moving in the camera field of view.

5. Never conduct maintenance work on a side shift mechanism while it is supporting the implement.
6. Side shift and steered disc mechanisms form pinch, trap and shear points. Be aware of these when carrying out maintenance.
7. Regularly check the condition of electrical cables, hydraulic hoses and fittings.
8. Do not allow other persons to ride on or work near an implement when it is in operation.
9. The optional tractor power supply cable has a 20Amp fuse fitted near to the battery terminals. This is for short circuit protection and must not be omitted. If connecting to an existing 12V power outlet, ensure that it is appropriately fused.
10. When routing the loom and power supply cables ensure that they do not cause a restriction or trip point in the cab.

5. Assembly

5.1 General Assembly

It is assumed here that the implement is fitted with a hydraulic side shift or disc steered system actuated by a **12V** solenoid operated directional valve taking less than **3 amps** when operated. It is further assumed that the hydraulic circuit includes the means to regulate the flow of oil and thus the rate of side shift or steering, unless a proportional steering valve option has been chosen.

Step 1 – Mounting the implement control box

The implement control box is best mounted centrally on the implement to reduce cable lengths. The metal box is water resistant to IP67, but we recommend providing a cover to protect against mechanical damage and direct rain. The box measures 260mm x 160mm x 91mm with 6.67mm diameter fixing holes at 240mm x 110mm centres. Minimum bend radius is 28mm for camera and CAN cables, 45mm for console cables.

Step 2 – Mounting side shift or steering sensors

Ensure sensors have a stroke greater than mechanism movement and are mounted symmetrically so that mid stroke of the sensor represents mid stroke of the implement. (Offset configurations are possible but best avoided in the interests of simplicity). Potentiometers should have a resistance of between **3K Ω** and **10K Ω** . Our standard linear potentiometers have a maximum resistance of **5K Ω** . It is also possible to use Hall effect-based position sensors provided their output range is within 0 - 5V. As standard sensor supply voltage is set to 5V. Alternatively, this can be set to 12V by changing a jumper on the microcontroller board within the implement module.

The implement module has inputs for two position sensors, steer and auxiliary. Standard side shift machines only use the steer input, but disc steered systems are able to measure both disc/wheel steering angle and free shift position. If a second free shift position sensor is fitted to the auxiliary input, DIP switch No 4 inside the implement should be set to OFF. See [Annex](#) for details. This ensures that the working screen light bar displays free shift position.

Step 3 – Odometry

There are five alternative ways to measure speed. The most popular uses vision based odometry derived from video images. Another uses a GPS based speed sensor. If an ISO 11786 socket is available on the tractor, that can also be used to supply both lift and odometric data, If an ISOBUS connection is available and the ISOBUS version of our implement module is installed our system can take lift and odometer data from the tractor's ISOBUS.

If none of those is satisfactory it is also possible to derive speed from a ground wheel fitted with teeth/spokes detected by a (NPN) proximity detector. Our standard proximity sensor picks up ferrous metals up to a gap of 4mm. We recommend that as a minimum a speed pulse is generated every 10cm of forward movement.

Step 4 – Mounting the lift and fold (optional) proximity sensor/microswitch

Lift and fold movements can be detected using either NPN type proximity detectors or microswitches. Lift sensors should be mounted on a depth wheel unit or adjacent to the tractor top link such that they are triggered when the implement is lifted. It is important that the lift sensor cannot be triggered spuriously, by passing over a wheel rut for example.

In the case of using an ISO 11786 socket or ISOBUS for hitch position, installation of a lift switch can be omitted. ISOBUS hitch lift trigger point can be set from the "Advanced settings and diagnostics" screen described in [Section 6.3](#).

Step 5 – Mounting the camera(s)

Typically, cameras are mounted on a vertical pole approximately 1.6m above soil level at an angle of approximately 40 degrees to the vertical (though both these can be refined during the commissioning process). It is important that the camera is held rigidly and square to the implement. It should be mounted over the centre of the crop rows to be followed. A second camera may be fitted on the other side of the implement to improve performance at field margins where crop failure, or severe weed infestation may have occurred near a headland. It also helps cope with converging drill bouts, especially when guiding implements with section control. Camera cable minimum bend radius is 28mm.

Normally by default cameras are mounted on a steered part of the frame. The guidance system acts to keep cameras aligned with crop rows along with any other tools attached to that frame.

It is also possible to create configurations allowing cameras to be mounted on a fixed part of the frame or tractor allowing the guidance system to steer the frame independently to keep tools aligned with crop rows. This feature can be useful for mid mounted implements where the tractor's front axle might obscure crop rows immediately ahead of the steered frame.

Step 6 – Connecting hydraulic valve solenoids and sensors

Route cables and hoses carefully ensuring they cannot become trapped or chaffed making allowance for normal movement such as side shift or implement lift.

Step 7 - Mounting the console

Mount the console in the tractor cab in a position where it can be clearly seen but does not obscure operator's visibility. Four M6 mounting holes on a square 100mm pitch at the console rear are designed to accept VESA standard brackets. We recommend "RAM" type ball and socket style mounting brackets, but other mounting methods are available.

Caution

- The console should be protected from severe vibration.
- The console is water resistant but should not be mounted where it will be exposed to direct rain.
- Minimum bend radius 45mm for console cables.

Step 8 – Hitching to the tractor

Position the tractor and implement on a level surface. Check that the tractor's lower link arms are evenly adjusted and hitch to the 3-point linkage points on the side shift frame.

Caution

- Once the 3-point linkage is correctly fitted stop the tractor and apply the handbrake.

Step 9 – Reducing free lateral movement

For side shift systems adjust stabiliser links to prevent lateral movement of the lower link arms to give the implement a rigid reference to steer against.

Caution

- For side shifting front mounted systems it is particularly important that there is no lateral movement in the linkage.
- For large rear mounted side shifting implements it is beneficial to use fixed discs attached to the non-side shifting part of the frame so that the moving section has a firm reference to push against. This also reduces lateral loads on the tractor. When using such fixed discs for stability, it is acceptable to have a small amount of lateral movement in the tractor lower link arms.

Step 10 – Levelling the implement

With the cultivator on the ground in its working position, adjust the top link so that the cultivator is level, front to rear and the camera pole(s) are vertical.

Step 11 – Connecting the implement cable to the console

The cable from the implement should be routed into the tractor cab and through to the console.

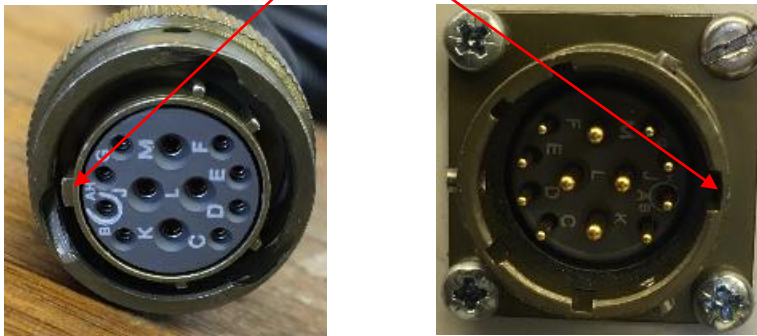
Caution

- Do not to allow the cable to restrict access to or exit from the cab or act as a trip point. Plug the multi pin plug into the socket in the bottom of the console.

Caution

- Note the correct alignment of the tabs in the plug and socket and avoid excessive force in pushing the connector together.

Ensure alignment tab and slot are lined up when inserting the plug into the socket



Caution

- Clipping the loom and hoses to the top link should help keep them clear of catch points.
- Make sure that the linkage can be operated over its full range without stretching or chaffing cables or hoses.

Step 12 – Connecting the power supply cable

The implement control box power supply cable should be connected to the tractors 12V auxiliary 3 pin “D” power socket. If that socket is not available, we offer cables to connect directly to the tractors battery which can provide either a female D plug or connect direct to the module.

It is important that any cable connecting direct to a tractor battery includes a 20amp fuse at the battery end for short circuit protection. Cigarette lighter sockets are definitely not suitable!

Caution

- Check polarity of power connections if fitting direct to the battery!
 - **BROWN = +12V**
 - **BLUE = 0V**

When the system is connected to 12V supply the console power button will flash every 5 seconds, indicating the console is ready to boot. If no flash occurs, please check connections for breaks.

Step 13 – Connecting the ISOBUS 12V power and data cable (ISOBUS Implements only)

Route the cable from the implement module to the tractor's ISOBUS socket.

Caution

- Do not allow the cable to restrict access to or exit from the cab or act as a trip point.
- Note the correct alignment of the tabs in the plug and socket and avoid excessive force in pushing the connector together.



Step 14 – Connect the hydraulic supply hoses

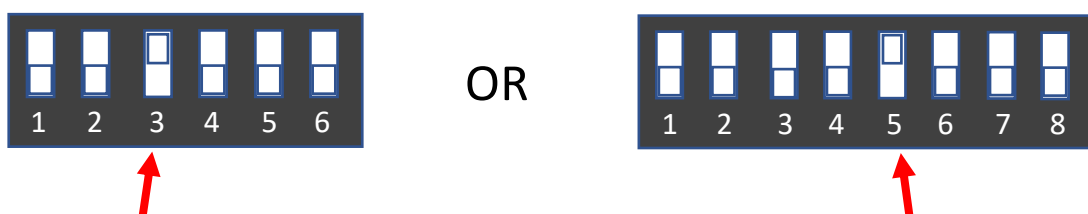
Connect the hydraulic supply hoses in such a way that they are not chaffed or over extended with full link movement. Attaching hoses to the top link is sometimes helpful.

Step 15 – Activating night operation lights or the ON while moving output

In addition to valve outputs the module is equipped with an extra output that can drive up to 3 amps that can be configured to either switch on when moving, potentially useful for band spraying, or on when switched on from the console. The latter being intended for activating night lights. Which mode the module operates in is determined by a DIP switch on the module right-hand side of the implement microcontroller PCB as outlined below.

To turn on the light option the switch should be in the “UP/ON” position.

For models of implement module with a 6 way DIP switch use switch No3 and for 8 switch models use switch No5.



5.2 Accessories and CANbus devices

5.2.1 Adding a remote manual control box (optional)

To add a remote manual box, plug the trailing cable into the implement module's CAN socket. Take care to ensure the cable is routed in a way avoids stretch and trap points.

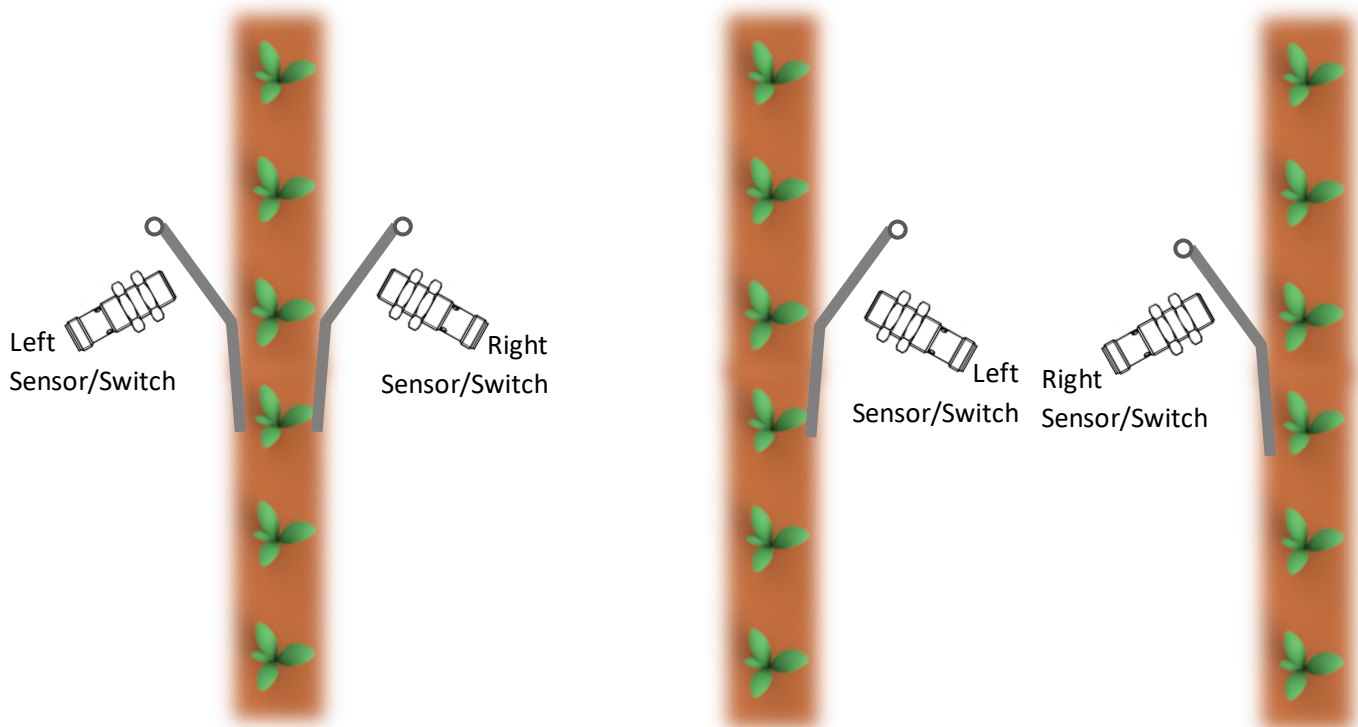
If you wish to add a remote manual control box to an implement that is already using the CAN socket for another function it will be necessary to add CAN output to the control box for that function. For example, on request feeler boxes can be equipped with a CAN output to facilitate both feeler and manual box capability on the same machine.

5.2.2 Adding feeler guidance (optional)

Feeler guidance requires mechanical feelers or "wands" to be fitted either side of a row of mature crop such that deviation from central alignment causes one or other of the feelers to be deflected. This deflection is sensed by a proximity detector connected to the feeler box. It follows then that two proximity sensors are required per row. One detects deviation to the left and the other deviation to the right.

Our feeler boxes have inputs for four proximity detectors so that one box can obtain guidance information from up to two rows. For more details on feeler guidance implementation please ask for our leaflet on that subject.

Feeler mechanical design needs to reflect the application, but they should be relatively light and mounted as far forward as possible with a lead in profile to assist with initial alignment. The dead band distance between points at which sensors are triggered is best made adjustable to accommodate crop growth. In principle a similar arrangement can be used to track a soil ridge or furrow using non-contact sensors. Proximity detectors can be mechanically arranged in several different ways, for example:



Proximity detectors need to be wired into the feeler box according to the diagram inside the box lid.

Plug the feeler box trailing cable into the implement module's CAN socket. Take care to ensure the cable is routed in a way avoids stretch and trap points.

5.2.3 Opto-isolated Input/Output Relay Board (optional)

This board takes up to eight inputs and provides an output that turns on when any of the inputs are activated. This is normally used to drive a dump/unloader valve to unload a hydraulic system when no hydraulic services are required. Its most common application is on implements equipped with tine raising.

Step 1 – Mounting Opto-isolated input/output board

Mount securely via the provided mounting holes in an IP65 or better enclosure to protect from mechanical damage and water ingress. It is also advised to provide a cover for this enclosure to protect from mechanical damage and direct rain.

Step 2 – Wiring multiple inputs to board

Inputs are opto-isolated so current draws are low requiring only a light wire gauge. Channels are not polarity dependant.

Step 3 – Wiring supply voltage and output device

Supply voltage and output device should be wired according to silk screen of board. Appropriate wire gauge should be used. Board is fused to 5A so outputs should not exceed this.

Before proceeding it is worth familiarising yourself with the working screen.

6. User Screens

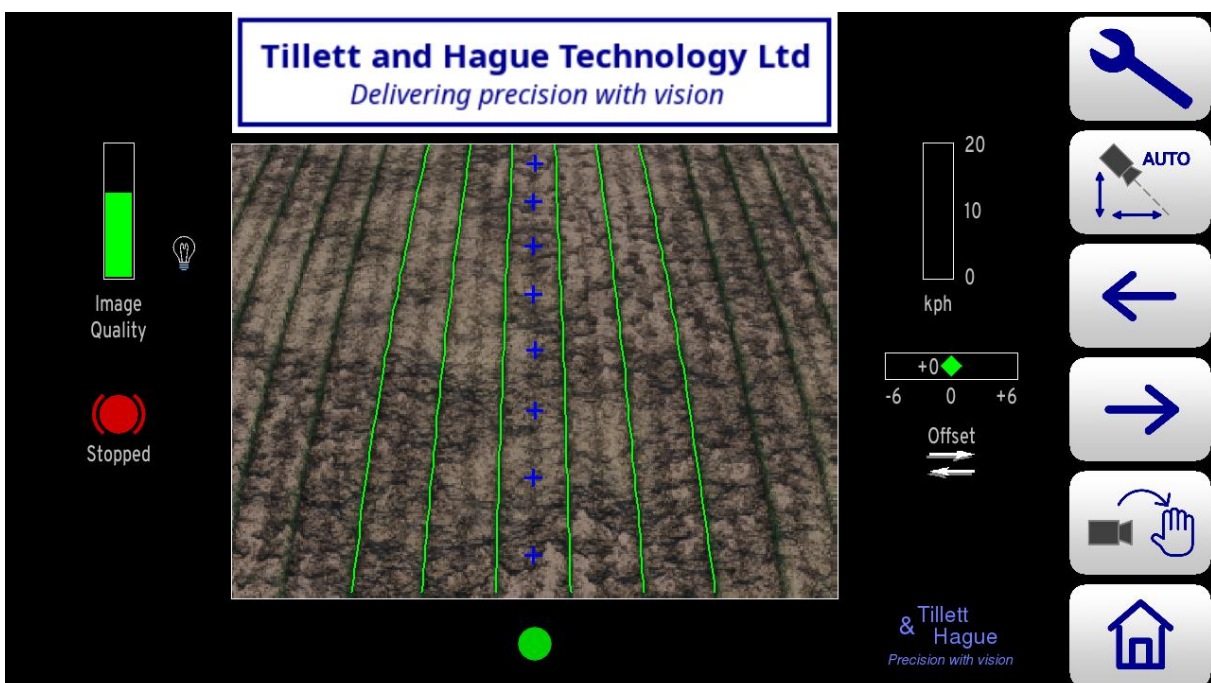


Start-up screen.

To turn the system on press the console button for a second or two until the button is illuminated. After some PC start-up text, the user is presented with a start-up screen offering the choice between starting the inter-row guidance system, going directly to the configuration editor, opening the service tools menu, or shutting down.

6.1 Working Screen

To get to the inter-row guidance working screen press the touch screen button with the crop rows symbol. When a press has been detected the touch screen button will become darker, though the function is only activated when your finger is released.



Working screen "in work" but stationary

The working screen has the following features:

- A live camera video image over which are superimposed two sets of markings. The first are series of eight coloured crosses arranged from the top to the bottom of the image. These represent local matches of the crop row template at different levels up the image. The second overlaid markings are green lines representing the overall template to which crop rows are matched. Their position is based on a succession of local matches represented by the crosses.
 - Blue crosses indicate a good match is found at that level. A series of blue crosses vertically aligned in a straight line indicate good tracking and accurate template alignment.
 - Yellow and red crosses indicate a poor match at that level that will not contribute much to overall template tracking. If many of the crosses are red or yellow performance will be compromised and you should follow the instructions in [Section 8](#) of this manual.
- Systems operating with multiple cameras will display live thumbnail video along the top of the display. Briefly touching on a thumbnail selects that image for the main display and other parameters such as offsets relate to the section that camera is fitted to. Additional cameras are normally used to provide extra guidance information, but it is also possible to configure cameras to provide a CCTV function.

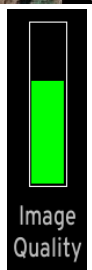
- Touching and holding on an image, or its thumbnail, stops images from that camera being used for guidance, making guidance solely reliant on any remaining cameras. When a camera is disabled in this way a red cross is superimposed over the image which remains live. Touching and holding again restores normal function.



- Briefly touching on the main video images switches to a full screen video mode. Guidance continues in this mode, but the information symbols, speed, position indicator etc are obscured. Touching again reverts to the normal size image.



- An image quality gauge to the left of the screen giving relative indication of likely tracking performance. The higher the green bar the better. A low bar indicates either a poor template match or poorly defined crop rows. Guidance will, under most circumstances, operate down to an indication of approximately 20% and sometimes even less albeit at reduced accuracy.



- If any of the crop colour options are enabled via the configuration editor a plant symbol will be shown at the top and to the right of the image quality gauge. The colour of the symbol gives an indication of the colour selection currently active. Touching on the plant symbol will pop up a crop colour selection tool. Pressing on one of the available buttons will select the crop colour.

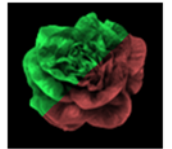


- In general use of colour options is discouraged as it offers more scope to degrade performance than enhance it. However, there are specific exceptions where colour options can help:

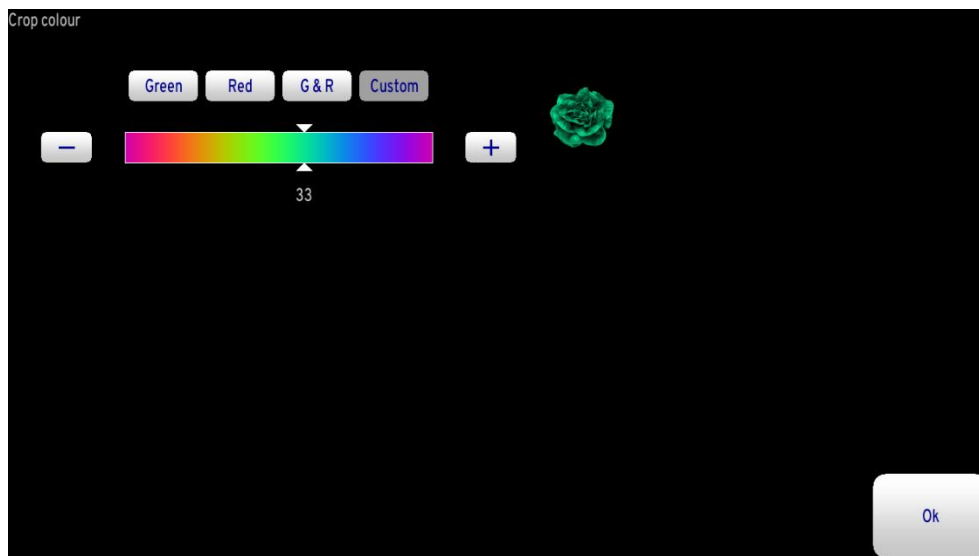
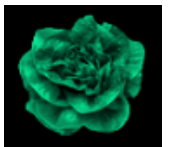
Red lettuce varieties benefit from the red option.



Red lettuce varieties showing a green growing centre sometimes benefit from the red and green (R&G) option.



If allium and brassica crops grow slightly blue as they mature, custom colour can improve performance. If a configuration enables custom colour, touching on the plant symbol in the working screen will pop up a screen offering a “Custom” option. That provides an adjustment tool using the +/- buttons, or touching the colour spectrum band to select a colour setting. A maximum of 30 is normally recommended.



Camera colour selection screen with custom colour enabled

- For plants with particularly unusual colours that cannot be tracked using any of the normal colour options as mentioned above, a camera with sensitivity in the Infra-Red can be fitted. These cameras are automatically detected and require no special colour adjustment. The benefit is that plant material is identified using brightness in the near infra-red rather than green. Not all live plant leaves are green, but they are all reflective in the near infra-red.

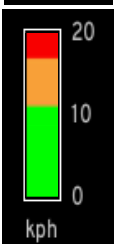
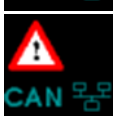
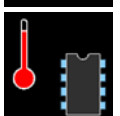
The new camera will also work on green crops, so it is possible to work on a wide variety of crop colours using a single camera without need to adjust colour settings. However, some performance sacrifices have been made to achieve this and so for customers with only green crops, we recommend using our normal RGB cameras. For night work Infra-Red cameras require illumination based on a hot filament e.g. halogen lights.

- If lights are configured a light bulb symbol is shown at the bottom right of the image quality bar. Touching the symbol turns lights on and the bulb yellow. To activate the lights option, see [Section 5.1 Step 15](#).



- Information symbols at the bottom left of the display:

- A warning triangle indicating poor tracking is displayed if estimated error in lateral position exceeds 25mm. The number between the arrows is the section to which the warning applies. On seeing this warning users should check performance on the ground. If enabled the warning triangle will be accompanied by an audible warning.
 - An implement lift symbol is displayed if the lift sensor detects the implement is lifted.
 - A circular red braked symbol is displayed if the implement is down but not moving.
 - A lightning bolt within brackets indicates a steer valve in an open circuit state.
 - A lightning bolt with lines radiating indicates a steer valve direct short.
 - Thermometer and computer chip Indicates the console processor is overheating.
 - A CAN warning triangle with a “?” or “!” indicated unknown, conflicting, or dropped CANbus messages suggesting CAN connection issues.



- A speed gauge on the right displays forward speed which should match tractor speed. By default, the speed bar is green up to 11kph and red over 15kph, which is normally a sensible operating limit, though guidance will continue at higher speeds. The scale is configurable.

- A green dot and red/green chevrons below the image indicate side shift or disc steer position. A red chevron with a vertical bar indicates the limit of travel has been reached. This should not be allowed to occur for extended periods.



- The fine offset gauge shows the amount of left or right bias set by the user. This is used to compensate for minor lateral camera misalignment but can also be useful on side slopes. By default, fine offset has six 1cm steps in either direction, though the number and size of steps is configurable.



- It is possible to reverse applied fine offset in a single press, using the fine offset flip tool that can be activated from the System information & diagnostics screen.



- If selected from the advanced settings and diagnostics page there is an option to automatically compensate for side slopes. This is an experimental feature that should not be enabled without consultation with your dealer.



The function of touch screen buttons located along the right of the screen are given below:

- Spanner symbol, this button accesses the setup screen ([Section 6.2](#)).
- **Briefly touching** the auto-learn button introduces a small amount of flexibility to camera height and angle/look ahead parameters for the camera currently displaying the main image. The system automatically adjusts those parameters to give a better template fit for that camera only. This machine learning can be performed whenever the machine is in work, either when stationary or moving.



For best results, only trigger auto camera pose estimation on flat ground when crop rows are straight and clearly defined.

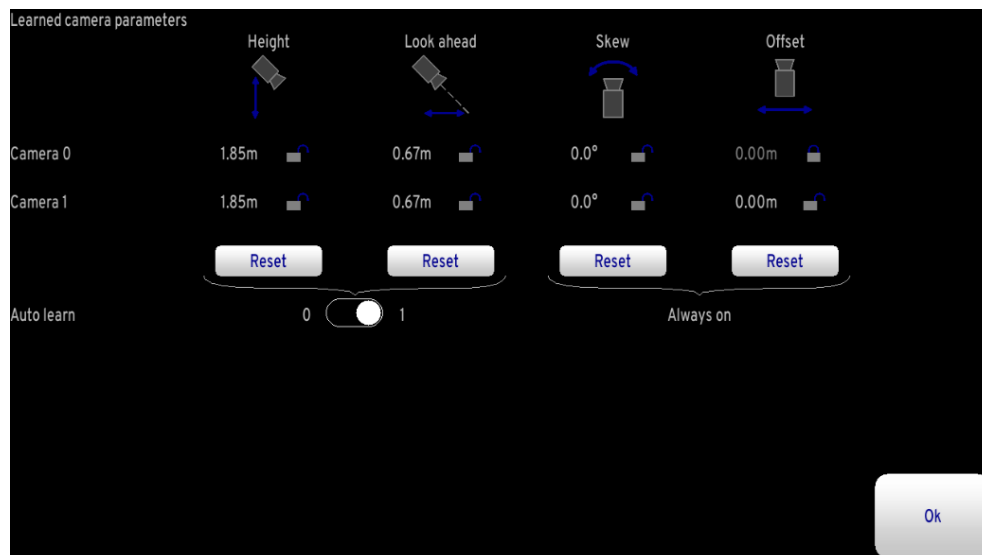
- **Touching and holding** the auto-learn button when moving has no effect, but when stationary opens a popup box displaying all four machine learned parameters. Those parameters are:

Camera height, the height of the camera (measured from the camera lens) to ground level.

Camera lookahead, a measure relating to camera angle to the vertical

Camera skew, a measure of camera angular misalignment in the horizontal plane.

Camera offset, the lateral error between two or more cameras fitted to the same section.



Learned camera parameters popup page with "Auto learn" switched on

For each parameter you can view its current value, and if required, reset height and look ahead to those entered in the active configuration, or in the case of skew and offset, reset to zero.

It is normally only necessary to do this major reset when a machine is being commissioned or after cameras have been moved in such a way that these parameters might have changed. You can reset to configuration values and relearn each parameter independently or they can all the reset and relearned together. In all cases the learning process should be effectively complete after about 100m of running after which the learned values should remain stable.

It is important that the learning process is conducted on flat ground when crop rows are straight and clearly defined.

If there are multiple cameras the reset operates on all of them, unlike the minor reset triggered by a brief touch of the Auto learn button, that only effects height and look ahead for the currently selected camera.

Auto machine learning of camera skew and offset is always on, though after approximately 100m or so of running they automatically converge to stable values that are effectively fixed. Auto-learning for camera height and lookahead estimation can be turned off using the touch toggle switch on the bottom line. Turning auto-learn off freezes parameters at their current learned values unless they are reset to configuration values. Turning auto-learn back on also resets to configuration values.

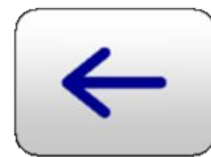
Caution

After resetting camera skew it will probably be necessary to adjust fine offset.

Camera skew influences camera offset so that resetting skew resets both figures for all cameras fitted. However, resetting offset does not automatically reset skew.

Camera skew values more than 3 degrees may indicate poor alignment, requiring improvement.

- ← moves fine offset left 1cm, or when in manual mode, side shifts or disc steered machines, 7% to the left.
- → moves fine offset right 1cm, or when in manual mode, side shifts or disc steered machines, 7% to the right.



Note

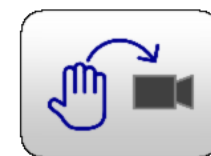
These arrows appear thicker when in manual mode.

- **Briefly touching** the button labelled with a Camera ↻ Hand icon disables vision steering allowing the user to move left or right manually in steps of 7% of position sensor stroke for each arrow button press. For disc steered machine with a freely sliding frame this is achieved by automatically steering discs to maintain the desired slide position. To prevent mechanical damage these functions only operate when lifted or moving.



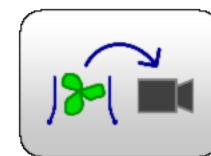
In manual mode green lines representing the template and purple cross hairs indicating the optical centre of the image are locked on the screen whilst retaining a live video image. These are useful when adjusting cameras ([Section 7 Step 6](#)).

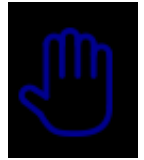
Return to vision guidance by **briefly** pressing same button again, now labelled with Hand ↻ Camera icon. By default, side shift/discs remain in the position they were placed manually until forward movement is detected. Alternatively, systems can be configured such that side shift/discs centralise on entry into manual mode (by turning on the “Centre when entering manual” option below).



For single section side shift machines by default manual control is retained when moving forward with a normal tracking screen shown so the operator can see if vision guidance is likely to be successful. Alternatively, it is also possible to configure the system to automatically activate camera guidance as soon as motion is detected (by turning on the “Leave manual when moving” option below).

- For machines with mechanical guidance feelers fitted the guidance mode button cycles between manual mode, feeler mode and vision guidance. In manual or feeler guidance mode the fine offset slide bar is replaced by a graphic symbol indicating the mode in use.





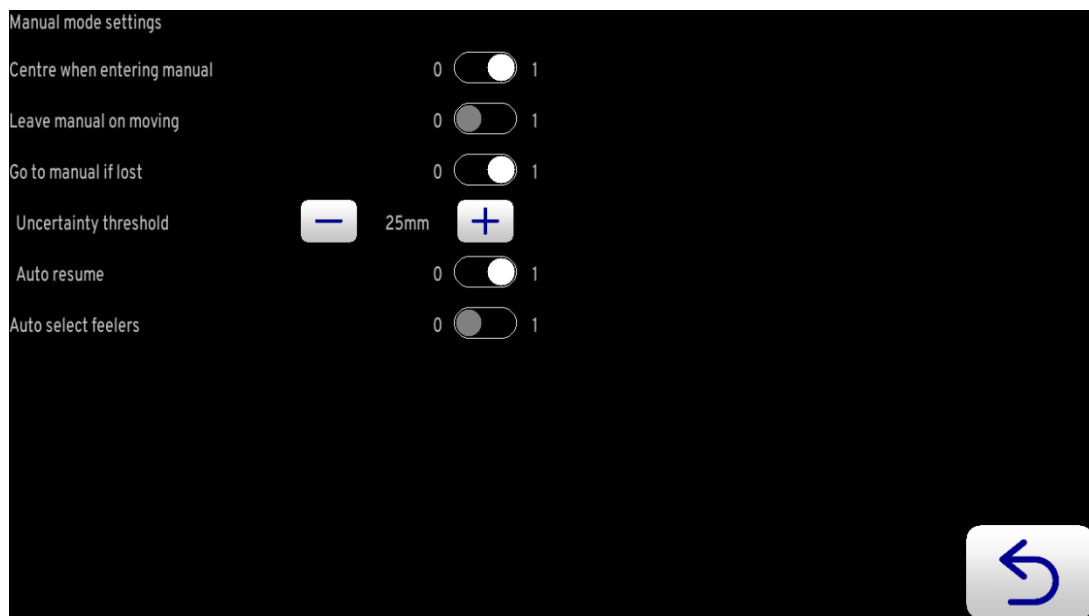
- If a manual box is fitted switching the box to manual overrides the console and a hand graphic replaces the fine offset slide bar.

- **Touching and holding** the manual button pops up a manual mode settings screen enabling you to change default behaviours as described above. Options are turned on and off by touching on switch icons.



If you turn the “Go to manual if lost” option on, so that the system automatically drops into manual when the guidance system is not confident of row position, you can also set the uncertainty threshold for that transition. The default figure of 25mm is normally satisfactory. Increasing that figure will make it less inclined to drop into manual and reducing it will make dropping into manual more likely. Having opted to drop out of vision guidance automatically you can also opt to resume vision guidance automatically once uncertainty is reduced by turning the “Auto resume” switch on.

If feelers are fitted, you have the option to mechanically arrange them such that when they are activated the system automatically drops out of vision guidance into feeler guidance. To select that option turn “Auto select feelers” on.



Manual mode settings popup screen

- From the working screen pressing the touch screen button with a house logo image returns you to the start-up screen.



6.2 The Setup Screen

The setup screen can be reached from the top right “spanner” touch screen button in the working screen. It enables users to select a prestored configuration for the crop they want to work on and to select an approximate height for the crop.



Configuration

Touching on the “Configuration” button provides a drop down list of configurations preloaded on to that machine. Touch on the one you want to select. The camera data displayed at the bottom of the screen reflects data from the selected configuration.

Camera

“Viewing” - Number of rows being used for tracking

“Spacing” - The row spacing between the *rows being viewed*.

“Height” - Distance vertically from lens to ground when in work

“Look ahead” – Horizontal distance along the ground from a point vertically below the lens to the centreline of sight (marked by cross hairs in manual mode).

This screen displays current camera height and look ahead values used for each camera along with their constituent configuration and learned correction values in brackets. If you wish configuration values to be the same as the learned values, you can edit those values in the editor.

If a suitable configuration is not available, it can be created using the configuration editor ([Section 10](#)).

Crop height

Similarly touching on the “Crop height” button provides a drop-down list of three options, small medium and large. Selecting the most appropriate will adjust template size to compensate for the crop canopy getting closer to the camera as it grows.

The definition of small, medium and large is scaled according to camera height in accordance with this table.

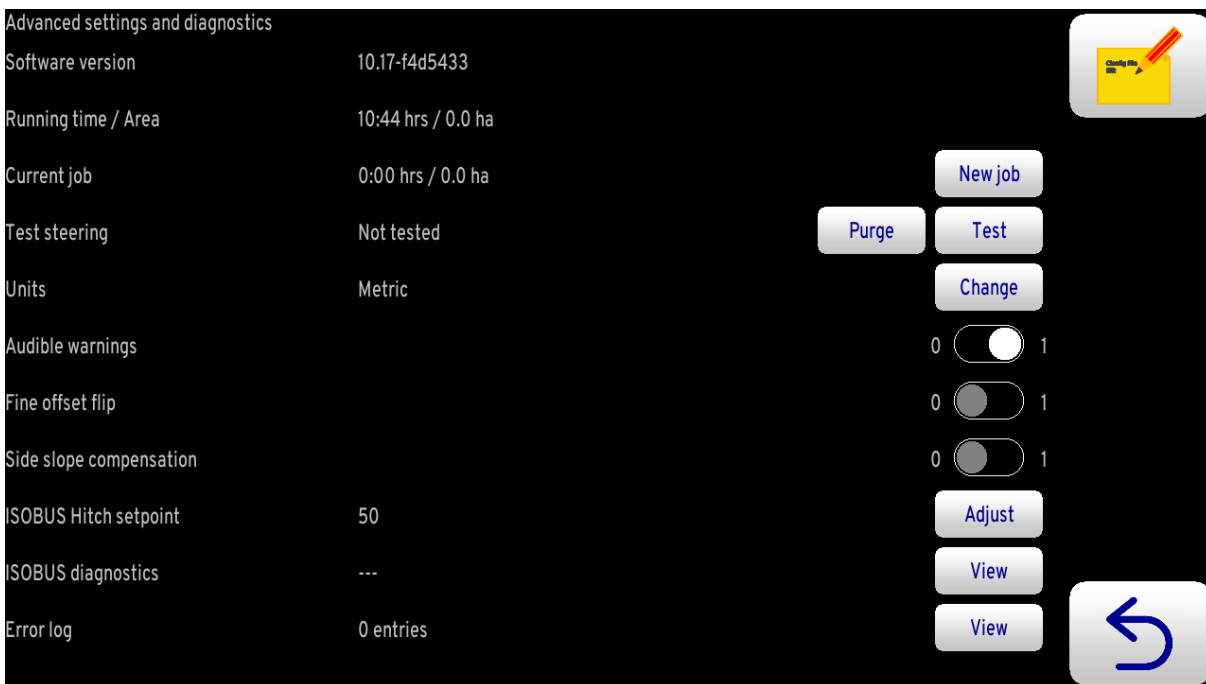
Camera Height	“Small”	“Medium”	“Large”
< 0.5m	0	5cm (2”)	>10 (4”)
0.5m – 1m	0	10cm (4”)	>20cm (8”)
>1m	<5cm (2”)	15cm (6”)	>30cm (12”)

On initial set up the default will be medium.

“Crop height” setting will be stored from your previous session for the next time you run that same configuration.

6.3 Advanced settings & diagnostics screen

This screen is reached from the setup screen by pressing the top right touch screen button labelled with a spanner ++ symbol.



The first two items on this screen are for information only and cannot be changed by the user. Area is based on distance travelled x implement width.

The remaining items on this screen are as follows:

Current job

Provides resettable counters for elapsed time and area treated.

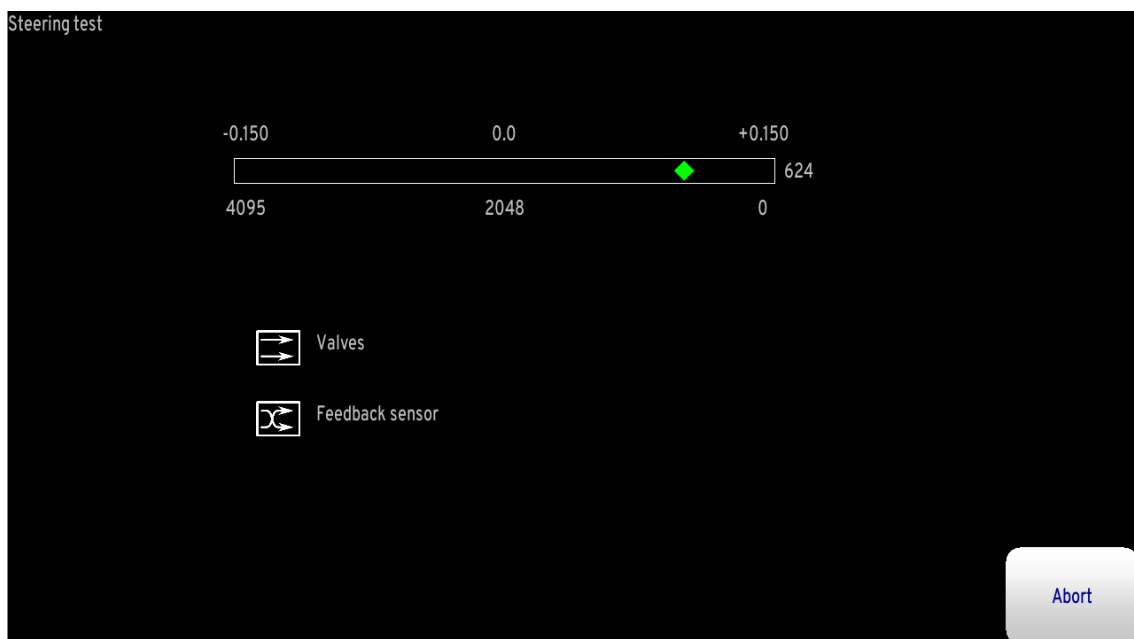
Test steering

Touching the “Test” button checks components and settings relating to side shift or disc steering. Included are micro-controller communication with the main computer, direction of hydraulic flow, rate of movement, side shift/disc potentiometer connection polarity and continuity over the stroke. It also detects mechanical obstructions preventing the expected full travel which result in the message “hit stop”. This is achieved by exercising the hydraulic cylinder and recording the response. It is therefore necessary to turn the hydraulic supply on. For multi section machines you are prompted to select which section to test. This test also serves as an initial calibration of steering direction (when viewed in the direction of travel) through a series of questions on screen.

If a proportional directional hydraulic valve is fitted (Switch No 3 of the 8 way DIP switch in the implement module should be set “ON”) the steering test includes an additional movement to calibrate rate of movement.

You can track the progress of the test via a graphical and numeric display of position sensor output as well as graphics indicating if the test has had to invert valve or sensor polarity.

Touching the “Purge” button drives steering valves for 10 seconds in one direction and then for 10 seconds in the opposite direction. This function can be used to purge air out of a steering system or to drive steering mechanism to an end stop to assist with synchronisation of left and right cylinders. The purge button is only available on request. Like the steering test, a graphical and numeric display shows position sensor output as the process operates.



Hydraulic steering test graphical progress screen (Purge screen is similar)

Caution

Ensure steering mechanism is clear of obstructions and people before running either function.

Units

Selecting toggles between metric and imperial units. This change affects all user screens and the configuration editor.

Audible Warnings

When the touch toggle switch is on, a buzzer inside the console sounds when warning symbols such as the poor tracking symbol appear on the working screen. The default is on.

Enable fine offset flip

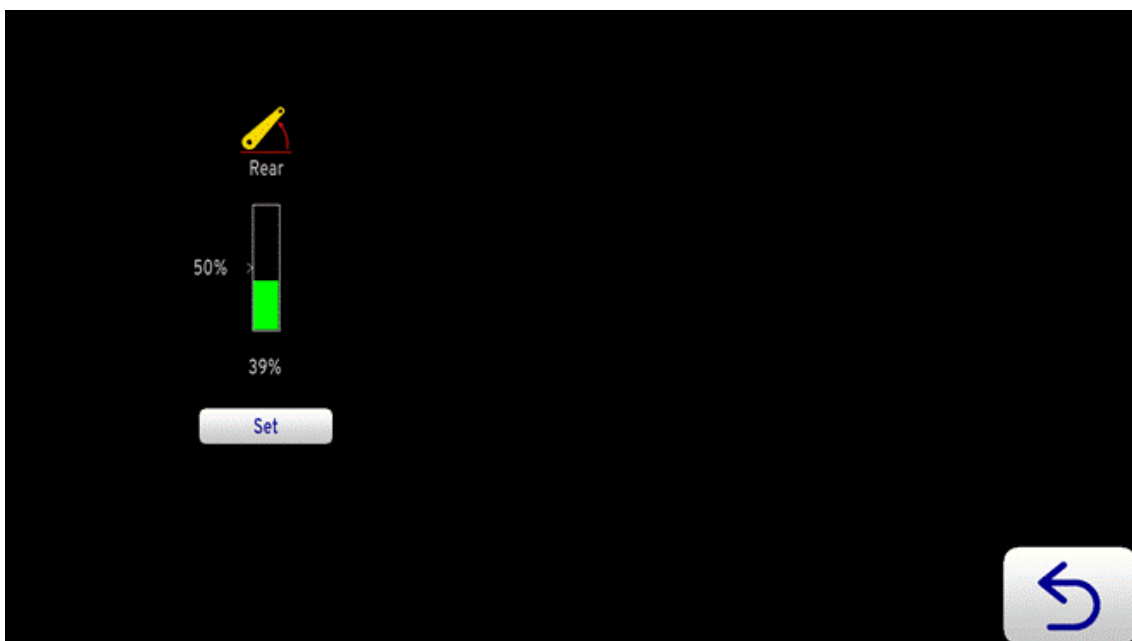
Selecting on adds a touch button on the working screen below the fine offset bar with opposing arrows which when touched flips fine offset direction. The default is off and should only be changed for work on side slopes or in cross winds.

Side slope compensation (an optional feature)

This experimental function is intended to automatically apply a lateral offset to compensate for sides slopes. Please [contact us](#) if you wish to try this feature.

ISOBUS Hitch Setpoint

Systems with an ISOBUS connection can set the trigger point for hitch lifted using this utility. When selected a screen with live graphics displays current hitch position as a green bar. Move the tractor hitch to the desired lift trigger position and press the set button. The trigger point has now been set and its value as a percentage of full stroke is displayed beneath the green bar. By default, hitch lift trigger position for both front and rear hitches will be 50% unless reset by the operator. Hitch setpoints are retained between sessions.



ISOBUS Diagnostics

This utility displays live ISOBUS data to check that a successful connection between tractor and implement has been achieved and that relevant tractor data is available. Live tractor data can be revealed and read using the arrow buttons to select the relevant page.



It is also possible to save a 20Mb log of the ISOBUS traffic to a USB device. This will be approximately the previous 10 to 40 minutes recorded depending on the loading of the bus. This file can then be sent to [Tillett and Hague](#) to aid in diagnosing ISOBUS connection issues between implement and tractor.

Error log

Is a log of automatically generated error messages (e.g. camera connections, microcontroller connections and excessive camera skew). Selecting “View” displays single line messages that can be helpful with diagnostics. Not all messages indicate serious faults. On exit you have the option to select “clear” which erases messages or close which returns to the advanced set up & diagnostics screen without erasing. These messages are saved between sessions.

Tip

When seeking advice over the telephone it is very useful to have an exact word for word record of any error messages and to make a note of numeric error codes.

To exit the status and diagnostics screen press the bottom right touch screen button labelled with a loop back arrow.



7. Initial setup and testing in the factory/yard

Step 1– Start the tractor and console

With the implement still on the ground check that the hydraulic supply is off, and all persons are well clear. Start the tractor, switch on the console and enter the working screen.



If the implement is lowered to its normal working position the “stopped” (red brake) symbol should be displayed, and the speed bar should read zero.

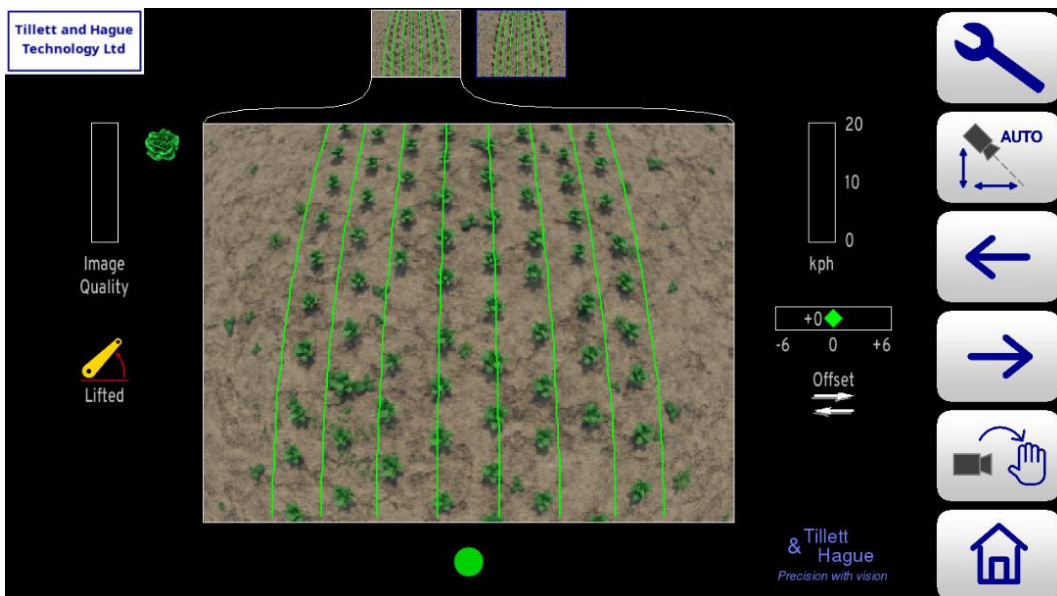


If the machine is configured to obtain speed via visual odometry and illumination is from artificial lights, there may be some spurious speed readings due to a strobing effect from those lights. This should not occur under natural lighting.

Taking care to ensure that the hydraulic supply is off, spinning the odometer wheel (if fitted) should register a green speed bar.



Lifting the implement should result in the “stopped” symbol being replaced by the “lifted” (yellow lift arms) symbol.



Console working screen showing the implement is lifted and centred


Step 2 – Checking hydraulic operation (for Non-proportional directional valves)

If adjustment is available, set the tractor's hydraulic flow rate to an appropriate level, typically 5 to 10% of full flow.

With the guidance system running, lift the implement clear of the ground and engage the hydraulic supply. Be ready to disengage immediately should a fault occur.

From the working screen touch the top right “spanner” button to enter the settings screen. Touch in the same area again (this time marked by a spanner++ symbol) to reach the advanced settings and diagnostics screen. Touch the “Test” button next to “Test Steering” line of the screen to start an interactive process that will set up the steering and prompt you should any adjustments be required. Left and right are defined when looking forward in the direction of travel.

At the end of the test the side shift or steered discs should centralise.

If you wish to test steering manually return to the working screen using the loop back button and touch on the button with the Camera  Hand icon. The hydraulic side shift/steering is now in manual mode and can be operated using the touch screen buttons labelled with left and right arrows. Each press of a button steps the side shift/steering by 7%. Repeated pressing and releasing (but not holding) will result in continuous travel up to the end of the stroke denoted by a red vertical bar. This procedure can be used to check that hydraulic flow is in the correct direction and that side shift rate is correct. A normal side shift rate would be 0.1m/s (e.g. 3s to travel a 0.3m stroke). To return to normal automatic mode press the same button (now with “camera” highlighted) again. The side shift/disc will stay in the position it was placed under manual control until the implement is lowered and raised again, or the machine starts to travel forward.

Caution

- Side shift/disc travel all the way to one side on lifting the implement may indicate that the hydraulic supply is connected the wrong way.
- Rapid side shift/disc oscillations back and forth about the central position indicates that the hydraulic flow rate is too high. The tractor flow control should be turned down. Alternatively, if fitted the hydraulic flow control valve on the implement may be adjusted.
- “Reverse oil flow” message can sometimes be falsely triggered by side-shift hydraulic flow control being fully closed.
- For safety only adjust the flow control valve with the implement on the ground and the tractor engine switched off.

Step 2 – Checking hydraulic operation (for Proportional directional valves)

The procedure for checking proportional hydraulic operation is the same as for a non-proportional valve except that sequence movements initiated by the “Test” function includes an additional full stroke movement to calibrate steering cylinder speed.

If the steering test with a proportional valve does not behave as expected check that the circuit board inside the implement module is version 2.6 or higher (see white silkscreen text at top right) and that switch No3 of the 8-way DIP switch is on (up position).



Step 3 (optional) – Activating a manual box

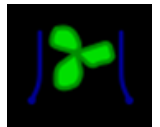
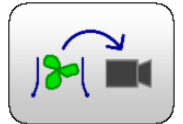
With the manual box switch in the off position the system will operate as normal. When the manual box is switched on a manual icon is displayed instead of the fine offset bar and vision guidance stops. The centrally sprung toggle switch now controls the side shift. With the toggle pushed to the left the side shift moves to the left and when pushed to the right it shifts right. Switching the box off resumes vision guidance.



Step 4 (optional) – Activating feeler guidance

To select feeler guidance, press the touch screen manual button twice until the feeler guidance icon is displayed instead of the fine offset bar.

When this symbol is displayed guidance is provided by the feelers. To resume vision guidance, press the same touch screen button again.



Step 5 (optional) – Activating night operation lights or the ON while moving output

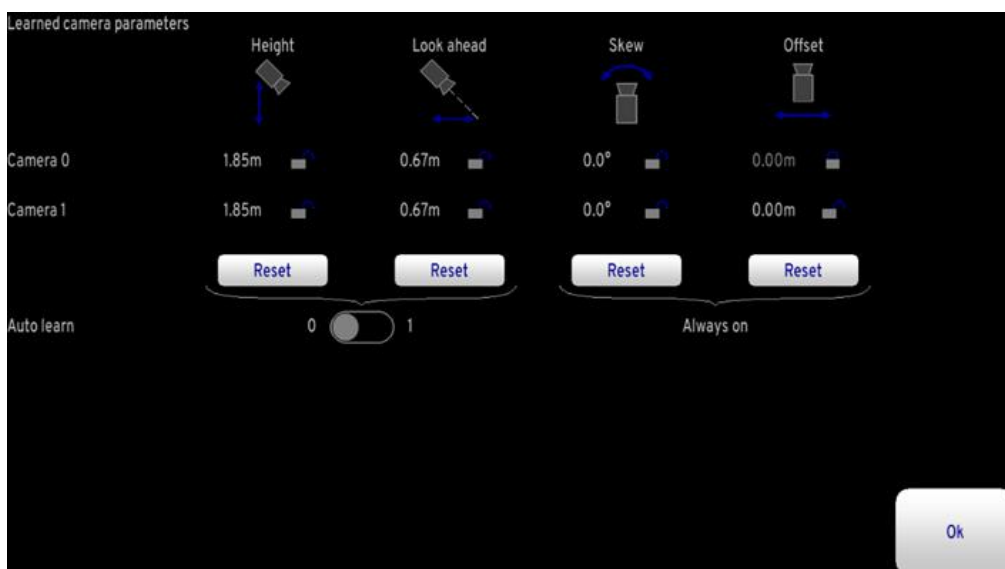
If the implement has been configured for night light operation ([Section 5.1 Step 15](#)) then there will be a light bulb icon to the bottom right of the image quality bar. Touching on it will turn the icon yellow and turn the lights on.

If the implement has not been configured for night light operation the same output can be connected to a solenoid valve which will be energised when the implement is moving.

Step 6 - Camera set up by measurement

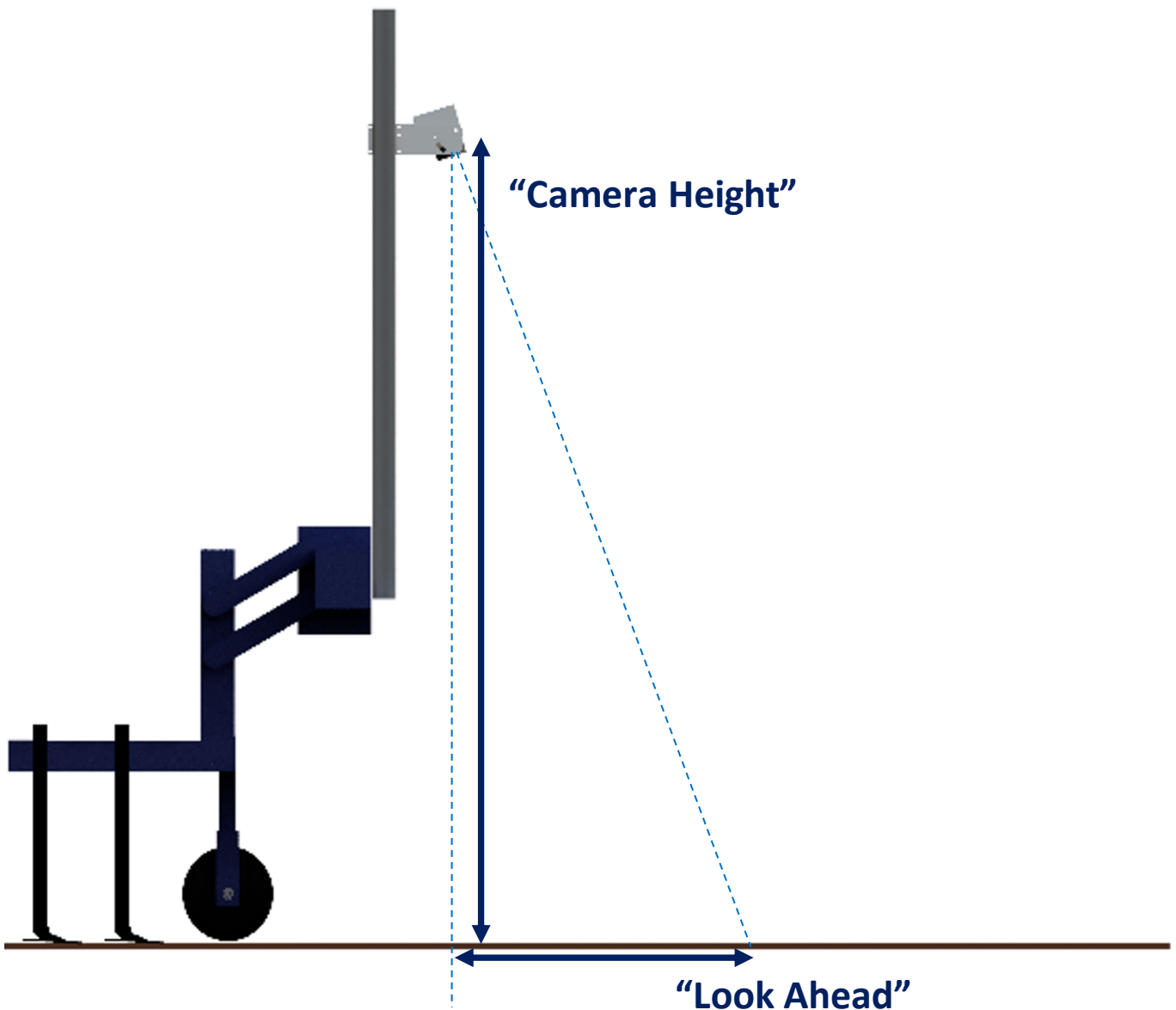
If you wish to set cameras up in the factory or farmyard without reference to crop rows you can do this with two simple measurements as follows:

Start by resetting all the learned parameters by pressing and holding the auto-learn button on the working screen to pop up a learned parameters setting page. Turn **off** the “Auto-learn” function using the toggle switch on the bottom line. This will reset camera height and look ahead to selected configuration values and prevents them from changing. Camera skew and offsets should also be reset to zero by touching on the appropriate “Reset” button. “Auto-learn” should remain off through the setup process and only turned on when setting off in the field.



Learned camera parameters pop up page with “Auto learn” switched off, and Skew and Offset reset to zero

From the working screen go into the “set up” screen by touching the spanner button. Select the configuration you require and make a note of “camera height” and “look ahead”.



Having checked that the implement is fully lowered and at its normal working depth adjust camera height so that it matches the figure given in the configuration. Now mark a point on the ground directly below the camera lens. From that point measure forward along the ground and place an object at the “look ahead” distance as illustrated in the diagram below. Return to the working screen and select manual mode. Purple cross hairs will appear in the image. Adjust camera inclination so that the cross hairs align with the object placed at the “look ahead” distance.

The camera is now correctly aligned.

Note: Remember to tighten any bolts loosened in the process of adjustment.

The machine is now ready to be taken to the field.

8. Getting to work in the field for initial running

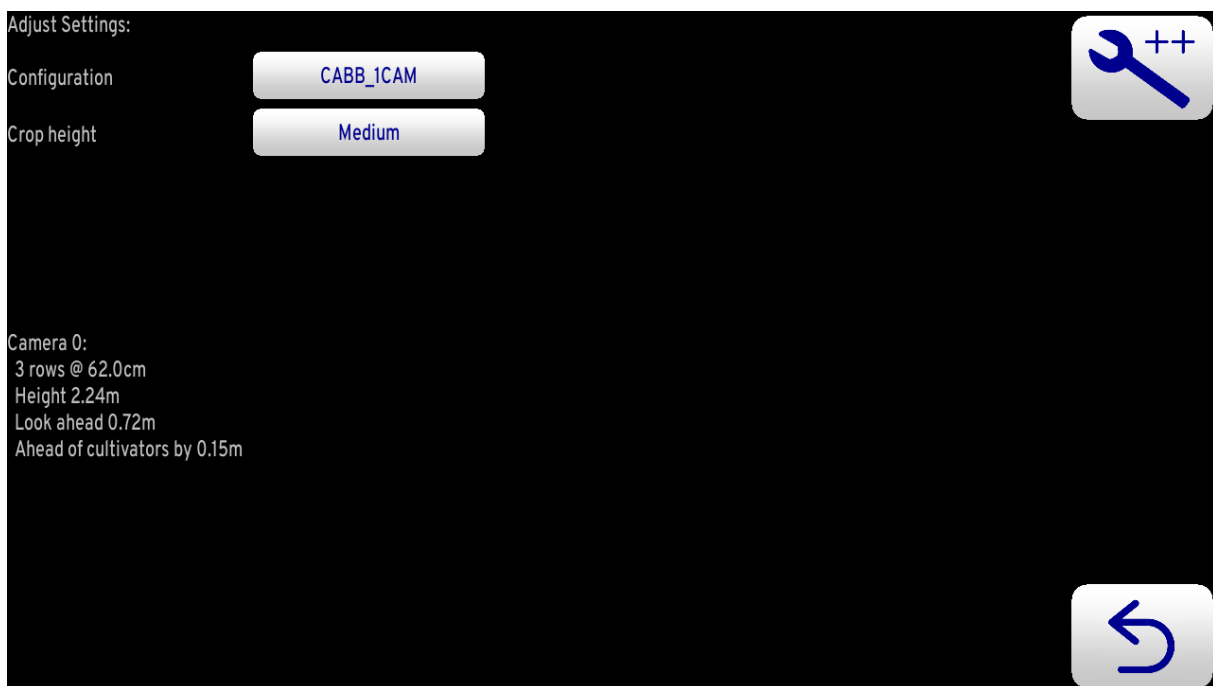
Reliable guidance requires an accurate match between the template, as illustrated by the superimposed green lines, to real crop rows as they appear in the live video image. The following steps outline how to get the best match and hence achieve the best guidance.

Tip

For the first few hundred meters of running a newly setup guidance system uses machine learning techniques to refine manually set parameters in such a way as to improve performance. For best results that learning phase should be carried out on flat ground when crop rows are straight and clearly defined. Once set up is complete more challenging situations can be tackled.

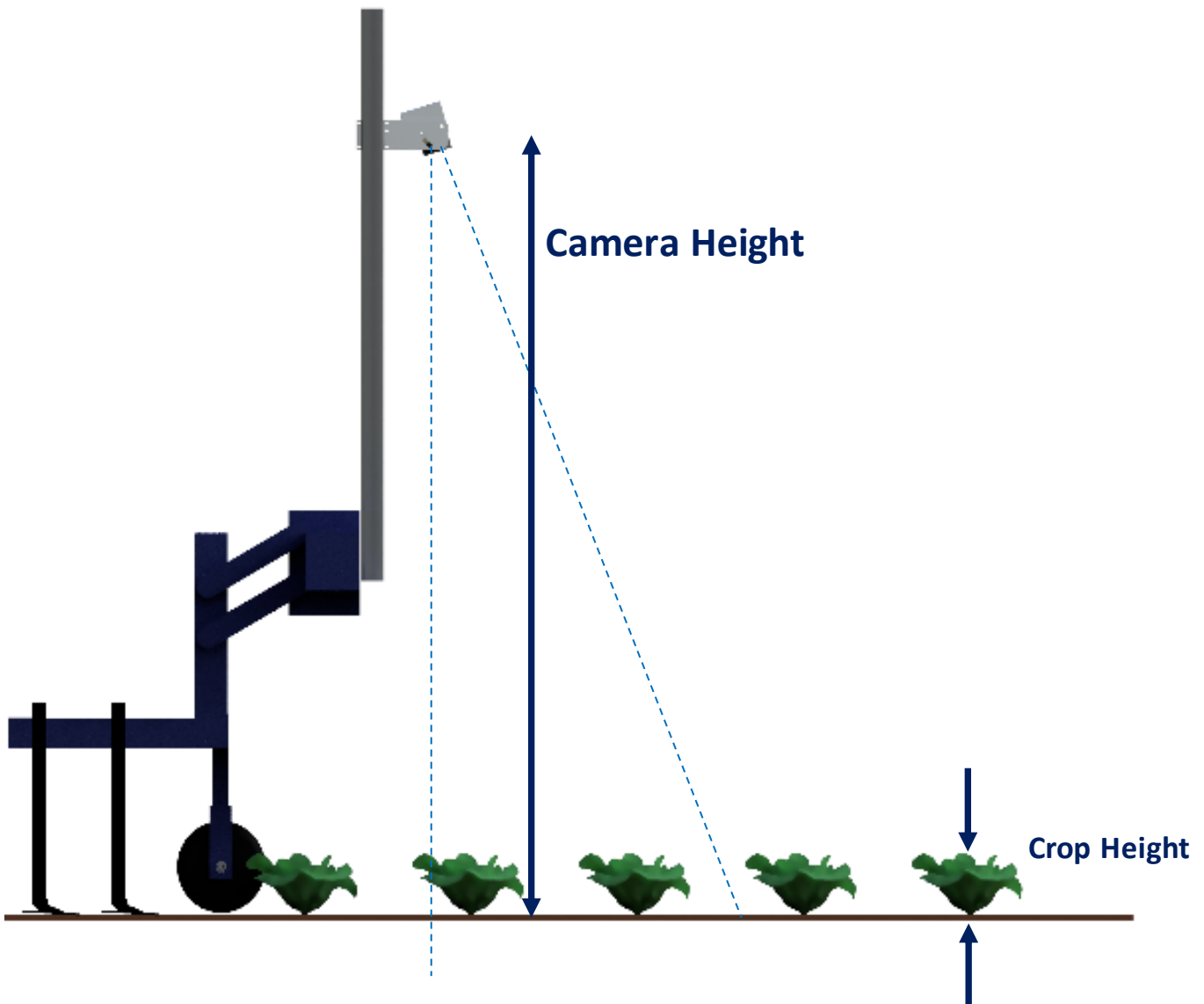
Step 1 – Selecting a configuration and crop size

From the working screen press touch screen setup button labelled with a spanner symbol. This switches the display to the setup screen.



Check selected configuration shown on the first line is the appropriate one and that the corresponding settings displayed at the bottom of the screen match crop geometry. E.g. that the number of rows viewed by the camera corresponds to the number being tracked and that row spacing on the ground correspond to the numbers on the screen.

Also, ensure that selected configuration settings match the number of cameras fitted.



If either crop or implement geometry do not match the selected configuration settings, select an alternative configuration. If a suitable configuration is not available refer to [Section 10](#) for instructions on how to create one.

The second line of this screen indicates crop size (height) settings under categories of small, medium and large selectable from the drop down list. The heights assigned to these labels vary with camera height and are displayed. Ensure that the selected option corresponds to the crop you are running in.

To return to the working screen press touch screen button labelled with a loop back arrow.



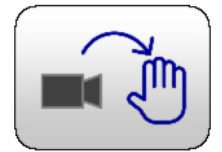
Step 2 – Checking camera height and inclination angle in the field

Draw into the crop and set the cultivator down onto a typical section of crop row. The cultivator should be level and set onto the rows as accurately, and as straight as possible with the camera at its normal operating height (as displayed in the “set up” screen).

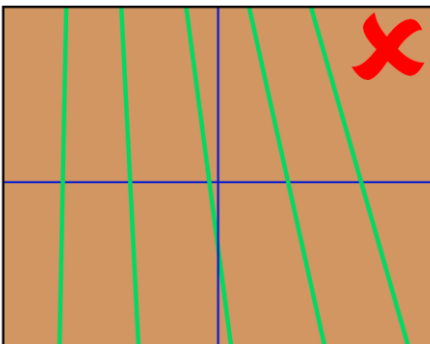
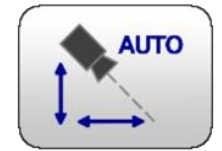
From the working screen centralise the fine offset bar so that the indicator is a diamond shape.



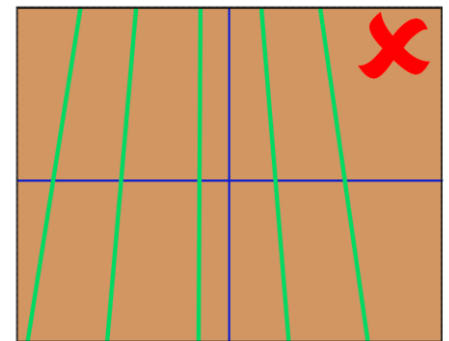
Press the touch screen button with the Camera ~ Hand icon to enter manual mode. The overlaid green lines representing the template should be fixed in the centre of the screen with no tracking crosses down the centre.



Press and hold the auto-learn button to pop up the Learned camera parameter screen. Ensure that “Auto-learn” is off and reset all four learned camera parameters (height, lookahead, skew and offset) which will eliminate any spurious figures that may have been learned prior to the initial set up process.



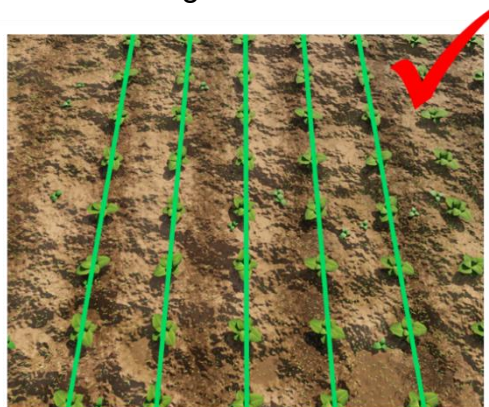
Overlaid green lines at an angle of more than 3 degrees indicate camera skew value needs resetting.



If the overlaid green lines are offset laterally from the real crop rows move camera(s) laterally until they are aligned.

If multiple cameras are fitted and the green template lines are aligned with the blue cross hairs in the left most camera but are laterally offset in any additional camera(s) check that camera offset(s) are zero and if necessary move the additional cameras to reduce these offset(s). If it is physically difficult to position the camera(s) perfectly it is acceptable to leave some offset. An appropriate compensating offset will be automatically created in the learning phase.

Green lines superimposed over the live image should match the crop rows as illustrated below.



Tip

If crop rows are difficult to see in the live video image you can enhance them by placing high visibility objects such as a strip of wood exactly over the row centre line.

If the green lines appear narrower or wider than real crop rows check the “crop size” selected and change if appropriate. If this does not resolve the problem, it may be that the camera height (measured from centre of lens to ground level) does not match the figure displayed. The best solution is to measure the correct position and move the camera accordingly. A less accurate, but often satisfactory alternative, is to adjust camera height until the “picture” looks correct.

In field camera set up by eye option



If the camera is too low, then the template will appear narrower than crop rows. In this case raise the camera.

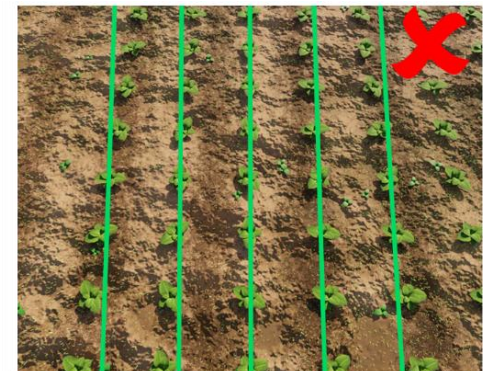


If the camera is too high, then the template will appear wider than crop rows. In this case lower the camera.

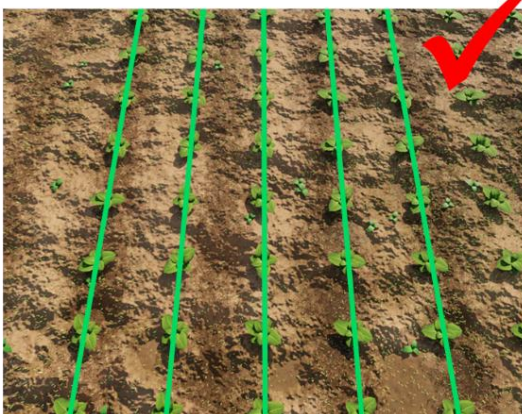
If the template matches mid screen, but not at the top or bottom, check that the implement is level. If it is camera inclination angle may need adjusting.



If template lines appear narrower than crop rows at the top of the image but wider at the bottom, rotate the camera up so it views further ahead.



If template lines appear wider than crop rows at the top of the image but narrower at the bottom, rotate the camera down so it views less far ahead.

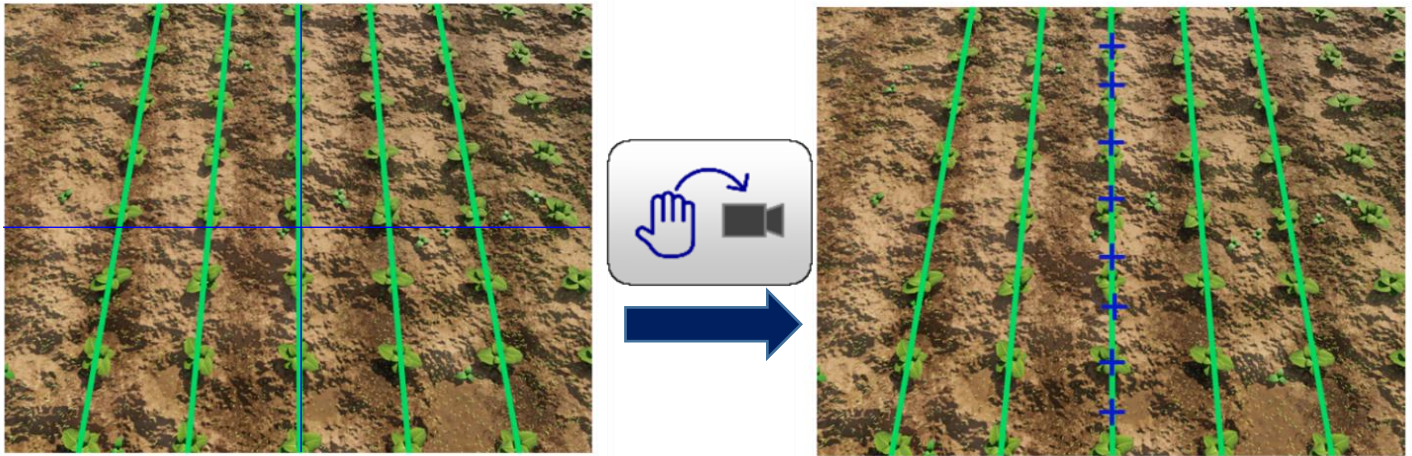


Best tracking will be achieved when template lines are centred on all the rows being tracked.

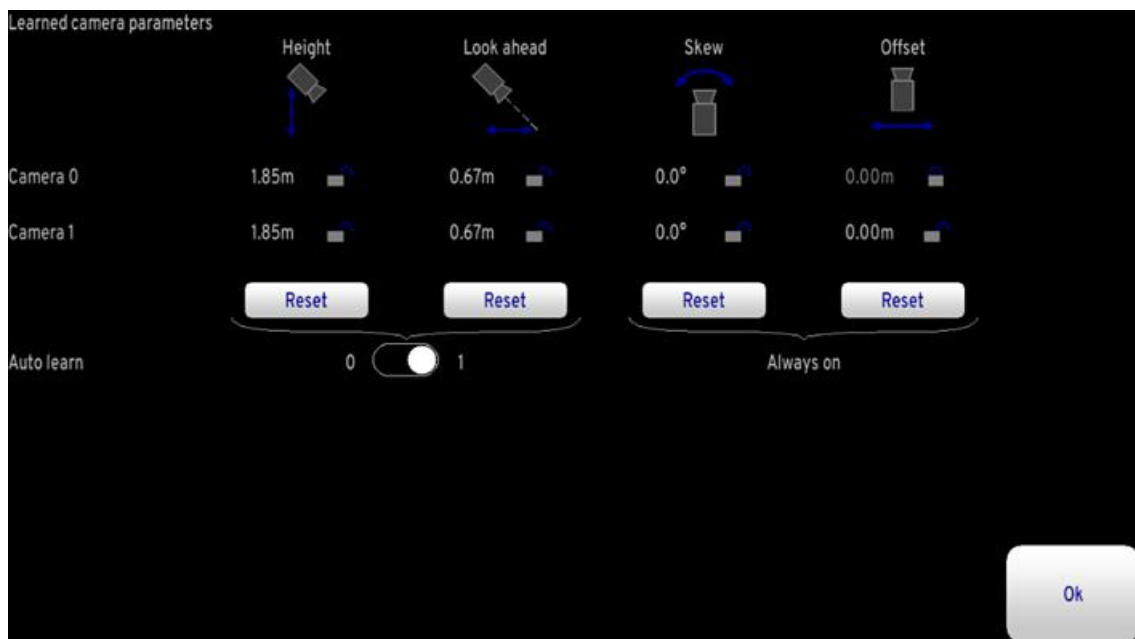
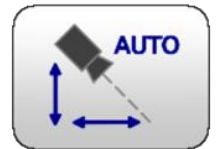
If you intend to turn auto-learn on you can tolerate minor misalignment at this stage.

Step 3 – Initial running and adjusting camera lateral position

When you are happy camera(s) are adequately aligned with a good template match use the Hand \rightarrow Camera icon button to resume camera guidance. You can be sure that the machine is ready for use if blue crosses have appeared down the centre of the display.



If you want auto learn to correct for minor template mismatch press and hold the auto-learn button to pop up the Learned parameters page. Use the toggle switch at the bottom of the page to turn “Auto learn” ON. Camera height and look ahead will be automatically adjusted to improve template match.



Learned camera parameters pop up page with “Auto learn” switched on

For initial runs almost all the crosses on live images should be coloured blue and form a relatively straight vertical line. If this is not the case, or a triangular tracking warning symbol is displayed, either the machine is not correctly set up, or crop rows are not sufficiently well defined for initial running.

If tracking appears good set off slowly. The implement should quickly align with crop rows. It is likely that after a short distance it will have settled at a small lateral offset. Small offsets can be corrected using the fine offset facility. Touch screen button labelled with left and right arrows adjust fine offset. Each press of an arrow key biases the side shift in steps of 1cm (3/8"). Continue down the field stopping occasionally to check lateral position. If the required fine offset exceeds the available number of steps the camera should be physically moved as described below.

It is the operator's responsibility to decide at which point the vision guidance system becomes 'lost'. If the system loses track of crop rows the operator should carefully guide the implement through to the next good reference.

Tillett & Hague Technology Ltd accept no responsibility for damage to or loss of crop whatsoever.

After approximately 100m of running all learned parameters should have converged and lateral bias stabilised. If fine offset is greater than two steps, we recommend physically moving the camera(s) along the tool frame by the equivalent distance and resetting fine offset to zero.

Tip

If fine offset is set to the left, then the camera should be moved right as viewed from behind looking forward.

Once you are confident tracking is accurate and reliable, forward speed can be increased. Mechanical interaction of cultivators and shields on the soil would normally limit speed to below 15 kph though guidance will continue to operate at higher speeds, albeit at reduced accuracy. The speed bar goes red at speeds above 15 kph and an overspeed event is logged in the error file. For lower speed applications it is possible to reduce speed gauge range ([Section 10](#)).

9. Notes on daily operation with a correctly set up machine

- Before operation check that electrical and hydraulic connections are secure and that there are no obstructions to side shift/disc movement. Check also that any hydraulic filter indicators fitted do not show that the filter is blocked.
- Check that the configuration selected on the setup screen is the appropriate one for the crop and that an appropriate crop height setting has been selected.
- On first setting the implement down in the field check that the green overlaid lines representing the template line up with crop rows and that overlaid blue crosses have appeared approximately central in the image. If the template lines are close to but not exactly matching real crop rows give a brief touch on the auto learn button. This will introduce a small amount of flexibility to camera height and lookahead which will be relearned as you move forward.
- Proceed with caution for first few meters checking that the on-screen speed gauge matches the tractors and that implement alignment is good. If performance is satisfactory speed can be increased. Tracking should be satisfactory up to 20 kph, though soil movement considerations will probably dictate a lower speed.
- Fine offset settings from previous sessions are saved and so there should not normally be any need to adjust this unless changes have been made to camera position.
- If there are changes effecting template match such as minor crop height differences, a brief touch on the auto-learn button when moving or stationary should bring template lines back into alignment.
- Side slopes may result in some lateral error due to the tractor “crabbing” across the slope. Normally this is not significant, but in extreme cases it may be necessary to use the fine offset function to compensate. If operating in this way remember to reverse the bias when heading in the opposite direction and to return to a neutral setting when stopping work or moving to a flat area. A similar technique can be used to compensate for crop bent laterally by a cross wind. The offset flip tool can be useful in these circumstances. NB do not touch the auto-learn button on side slopes.
- Each time the implement is lifted at row ends it will centralise ready for the next run.
- Vision guidance works in low light levels, but for full night operation lights are required.
- At the end of the day shut down the system by pressing the touch screen button with the power button logo and the system will shut down automatically. The power button LED will go out but will continue to flash every 5 sec indicating that power is still applied via the implement. In this state current draw is negligible.

10. Configuration editor

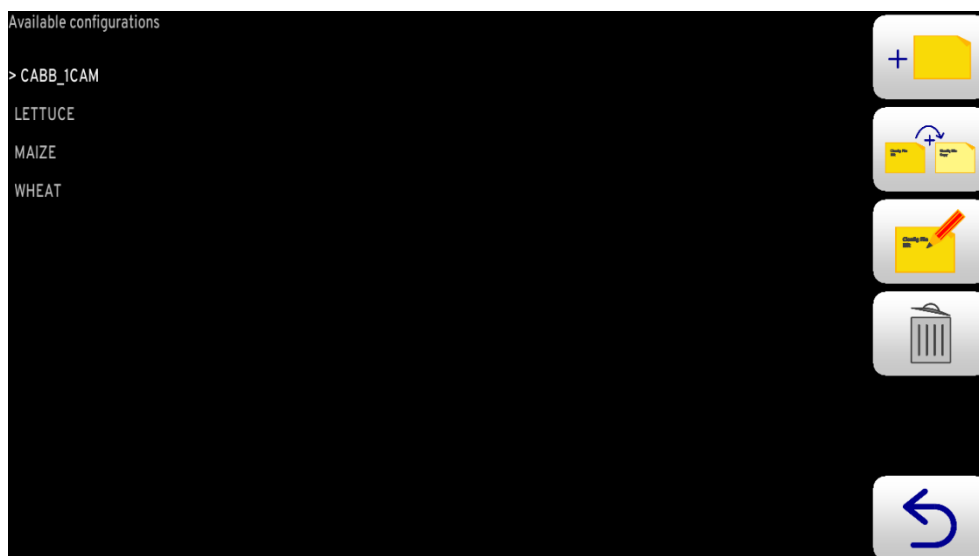
Configurations store information relating to a specific crop planting pattern and implement/tractor geometry that is necessary for row tracking. Each combination of a different crop pattern or implement geometry requires its own configuration.

The configuration editor allows experienced users to create and edit configurations. It is reached from either the Home or Advanced settings and diagnostics screens by pressing touch screen button labelled with a file and pen symbol. Users are required to enter a PIN to prevent accidental entry to the editor. The default is 1,2,3,4.

The editor is multilingual, though translations are not available in all languages. Where translations are not available, English will be displayed. Use of graphical symbols makes some functions independent of language.

The editor uses the touchscreen for navigation and data entry.

Overview of screen display and how to edit configurations



On entry to the configuration editor users are presented with a list of available pre-entered configurations. Touching on a configuration name selects it, highlighting with a change in intensity or colour and prefixes it with a “>” character.

Buttons on the right-hand side of the screen perform actions on the selected file, create new files, or change language settings.

- The top right button with a drawing of a single file and a “+” symbol creates a new configuration. **NB It is very rarely advisable for users to create a new configuration from defaults in this way. It is usually easier and safer to use the copy function (see below) to create a new configuration based on one that was factory installed and is already known to work.** If pressed users are presented with a series of choices regarding the type of machine that they want to create a configuration for. Following these choices will eventually lead to a default configuration that offers the best starting point for a new configuration. The newly created configuration will be added to the list, given the name “new” and selected ready for editing.
- The second button down depicting two files copies the selected configuration and adds that copy to the list with the name “new”. It is selected and ready for editing. **This is the preferred method for creating new configurations on a working machine.**

- The third button down depicting a file and a pen starts the editing process on the selected configuration, presenting a list of parameters that are available for editing.
- The fourth button down on the top configuration editor screen depicting a bin deletes the selected configuration.
- The bottom button labelled with a loop back arrow returns to the start screen.

Note: When you next run the system you need to select the appropriate configuration as editing a configuration does not automatically select it.

Settings available from the standard editor



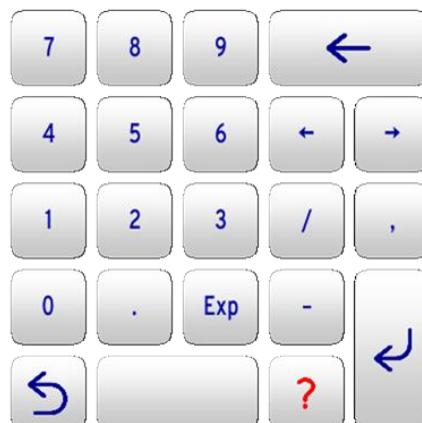
Configuration editor screen with standard settings selected

In editing mode three buttons are present at the bottom right of the screen:

- The top button marked with a spanner “++” symbol selects the advanced version of the editor. This offers a wider range of settings, but is rarely necessary under normal circumstances and should only be used with caution. See below for the additional functions offered in the advanced editor.
- The second button from the bottom switches between metric and imperial units.
- The bottom button labelled with a loop back arrow returns users to the next level up.

Touching on an item either pops up an appropriate keyboard (Letters for editing names, numeric for entering numbers) or presents another lower level list of parameters to select from. To remove the keyboard from the screen, press it's return key.

Touching the keyboard **?** key gives context relevant help. Please make use of this facility. It can be very helpful.

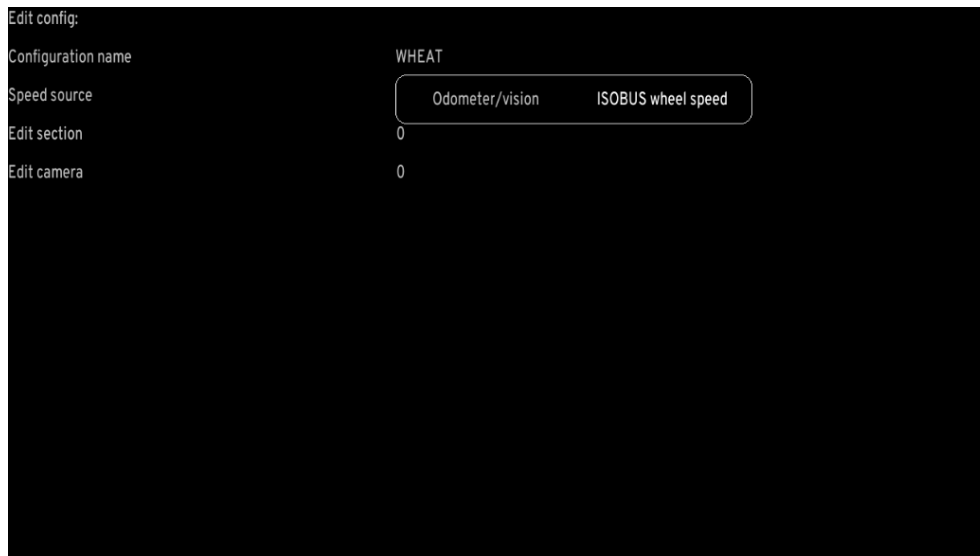


Numeric keypad with “?” Help function

General settings

The first provides an opportunity to change the configuration name. This can be up to 10 characters long and should be meaningful to the operator.

The second setting of “Speed Source” allows for selection between odometer input source to be derived from ISOBUS tractor wheel speed or Microcontroller/Visual odometer input.



Configuration editor top page with selection of speed source for ISOBUS system



Configuration editor top page for NON ISOBUS system

“**Odometer scale**” relates to distance travelled between counts from the odometer wheel encoder. It is calculated from the pulses per revolution (PPR) from the ground engaging wheel diameter according to the formula: $\pi \times \text{Wheel diameter} / \text{PPR}$.

Typically, there will be approximately 12 teeth or studs on a wheel making $PPR = 12 \cdot \pi = 3.14$. So, for example a 0.3m diameter wheel with 12 teeth would have an odometer scale = $3.14 \times 0.3 / 12 = 0.0785$ m/bit.

Tip

Odometer scale required for ISO11786 input is 0.00769m/bit

Note

If configuration specifies “ISOBUS wheel speed” as odometer source, odometer scale will not be displayed.

The remaining categories of settings relate to machine subcomponents. It is possible to have more than one of these subcomponents on a single machine. For example, a machine may have two or more cameras so there will be the option to edit settings for each of these cameras independently. For reasons relating to internal computing conventions numbering of these subcomponents always starts at zero, e.g. the first camera has index number 0 and the second 1.

To edit settings for any of these subcomponent’s touch on the blue index number in “[]” for the subcomponent that you wish to edit. This will take you into the edit screen for that particular component. Once you have completed editing that subcomponent you can return to the previous screen by pressing the button with a loop back arrow.

Section settings

A section is defined as a frame that has independent steering. Most implements will have only one section. However, it is possible to have an implement with up to four independently steered sections. This is useful when it is required to span multiple drill/transplanter bouts.

A description of the section type is displayed in brackets at the top of the page. Types include side-shift (front/rear), disc steered, steerable draw bar, vehicle and mid-mounted fixed camera side-shift. If creating a configuration from a default file, ensure correct section type is selected for your application. Multi-section implements can include different section types.



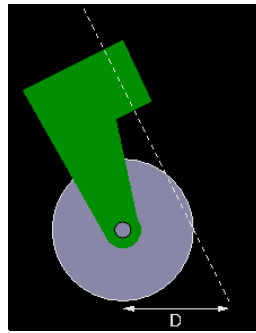
Configuration “Section” standard editor screen for a rear mount side shift machine

The settings are:

“**Width**” is the working width of that section and is only used to calculate area worked.

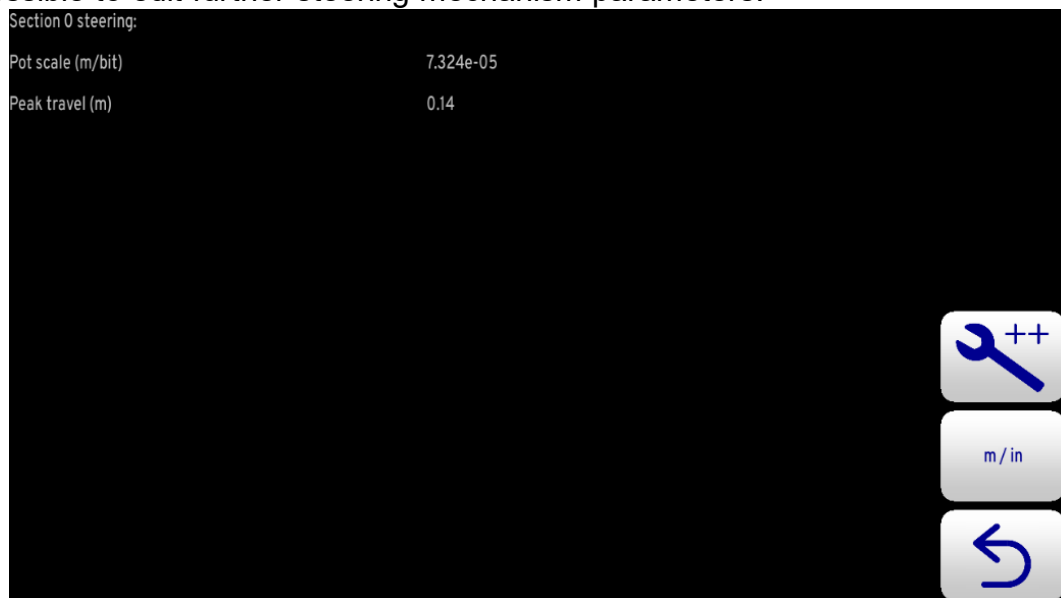
“**Cameras mounted**” which allocates which cameras are fitted to that section, e.g. 0 for one camera, 0,1 if two are fitted.

And for disc steered machines only. **“Steering arm length”** (distance D in figure below),



“Steering arm length” D

It is also possible to edit further steering mechanism parameters.



Configuration “Steering parameters” standard editor screen

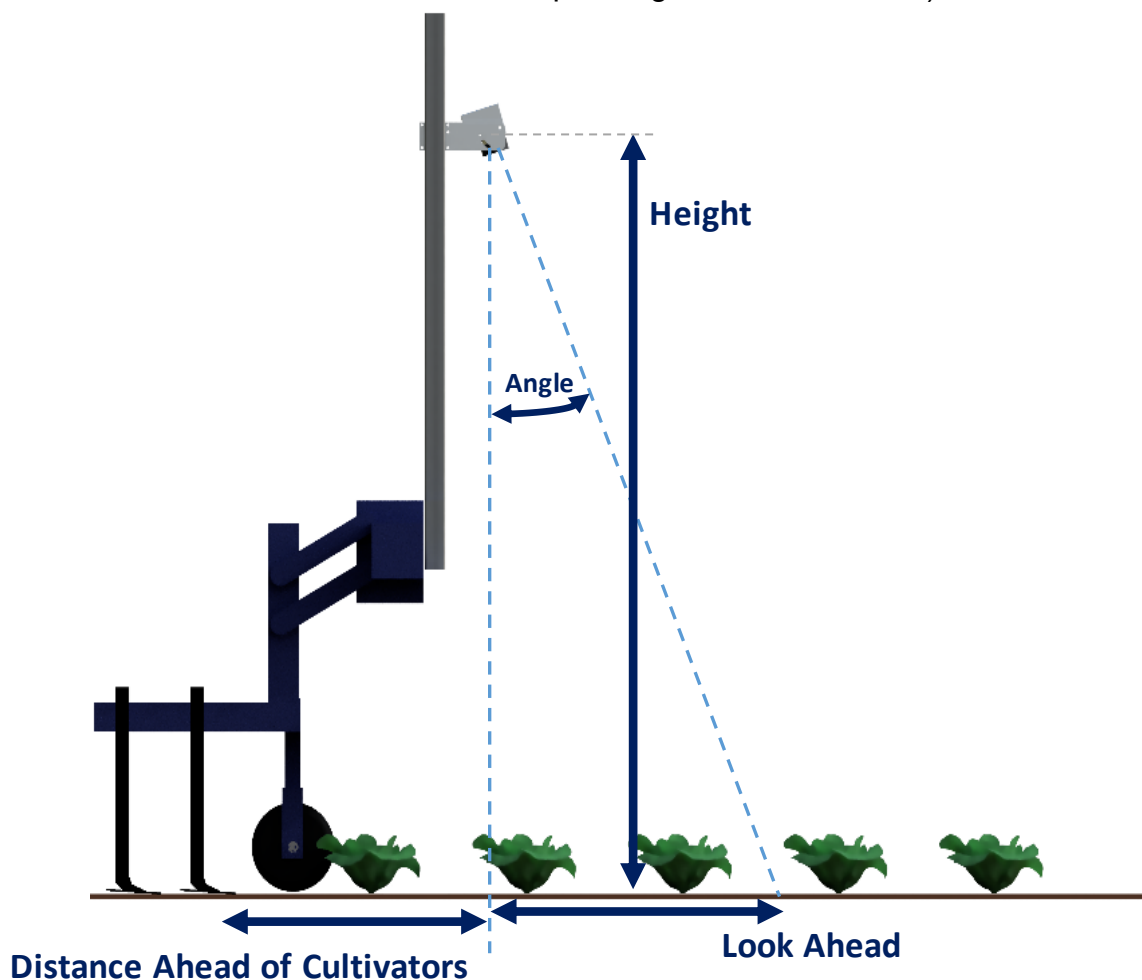
For side shift machines using a linear position sensor **“Pot scale”** is derived by taking full sensor stroke in meters and dividing by the digital range in bits. Our electronics accepts signals from 0V to 5V and use a 12bit converter i.e., 4096 bits. A potentiometer driven by our 5V reference will provide a 0-5V output giving a 0 – 4096 digital scale. For a 0.5m potentiometer that would be $0.5\text{m}/4096 = 0.00012207 \text{ m/bit}$. For a within cylinder position sensor with a 0.5V to 4.5V output then the digital scale would be 409 – 3687, a range of 3278 bits, so a 0.5m stroke position sensor would have a scale $0.5\text{m}/3278 = 0.00015253 \text{ m/bit}$.

“Peak travel” is measured from central position, usually set to be just under half total sensor stroke.

For disc steer machines peak travel becomes maximum angular deflection in degrees from the central position and Pot scale becomes the full rotary stroke of the rotary position sensor in degrees divided by 4086 (for a 0-5V output).

Camera settings

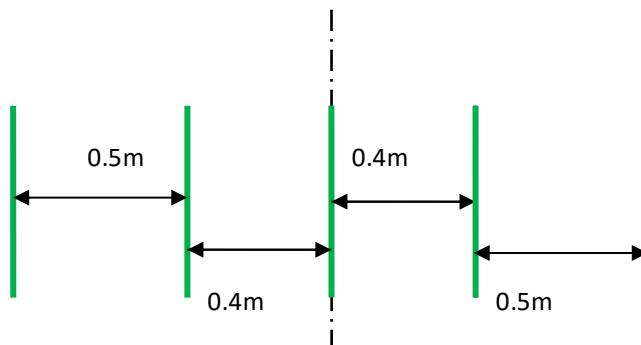
The first three settings relate to camera mounting geometry as illustrated below. **“Camera height”** is the vertical distance in meters (or inches with imperial units set) from ground level to the camera lens when the implement is at its normal working height. **“Look ahead”** is the horizontal distance from a point directly below the centre of the camera lens to the centre of the image in the ground plane (depicted by cross hairs in “manual” mode). **“Angle”** is the angle in degrees between the centre line of the camera’s view to the vertical. It is directly related to “Look ahead” by geometry. Camera alignment can be defined by editing either figure. The other one will adjust automatically so you only need enter the most convenient to measure. **“Distance ahead of cultivators”** is the horizontal distance in meters (or inches with imperial units set) from a point vertically below the camera lens back to the cultivator blades. (If In-row software is installed this distance is referred to as “Distance ahead of rotors/nozzles” even if operating in inter-row mode)



The next settings relate to what is seen in the image. The number of rows and their spacing. The number of rows entered here determines how many rows are used to construct the template. Spacing between rows is normally uniform across the field of view and is therefore a single figure. However, some crop geometries with a number of different row spacing’s in the same scene require a more complex arrangement. Syntax for this is based on the assumption that the pattern is symmetrical about the centre line and starts with the central row spacing working out to the edge. Figures are comma delimited. In the case of an even number of rows the first figure is always the whole row spacing, not the distance from the centre line to the next row. The following examples cover likely configurations.

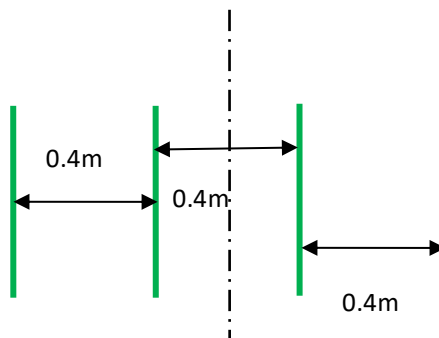
Odd no of rows irregular spacing example

Rows 5
Spacing 0.4,0.5



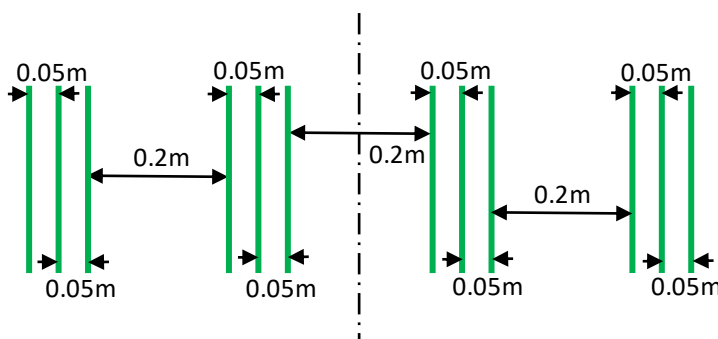
Even no of rows regular spacing example

Rows 4
Spacing 0.4

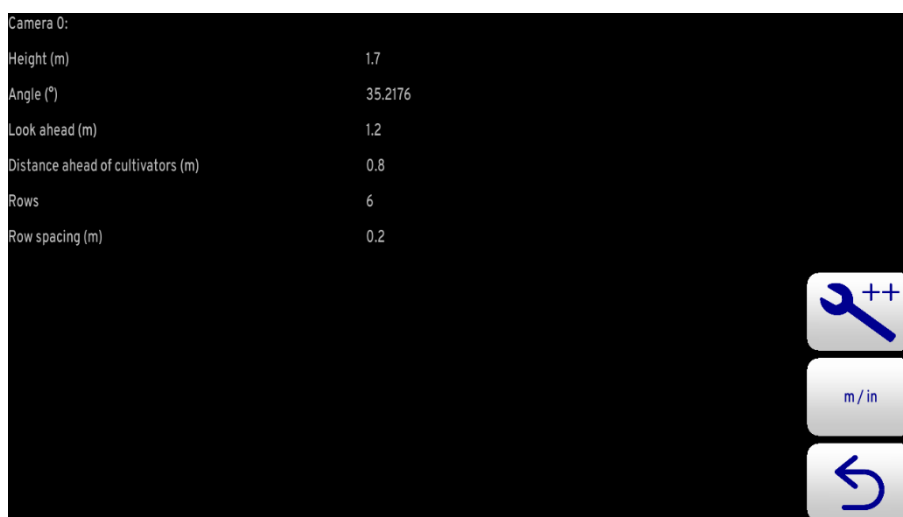


Grouped sets of rows example

Rows 12
Spacing 0.2,0.05,0.05,0.2,0.05,0.05



NB In the special case of following only one row the most accurate tracking will be achieved with row spacing set to between two and three times crop foliage width with an absolute minimum of 20cm.



Configuration "Camera" standard editor screen

Tip Context sensitive help is available within the configuration editor for most parameters by pressing the red "?" touchscreen keyboard key.

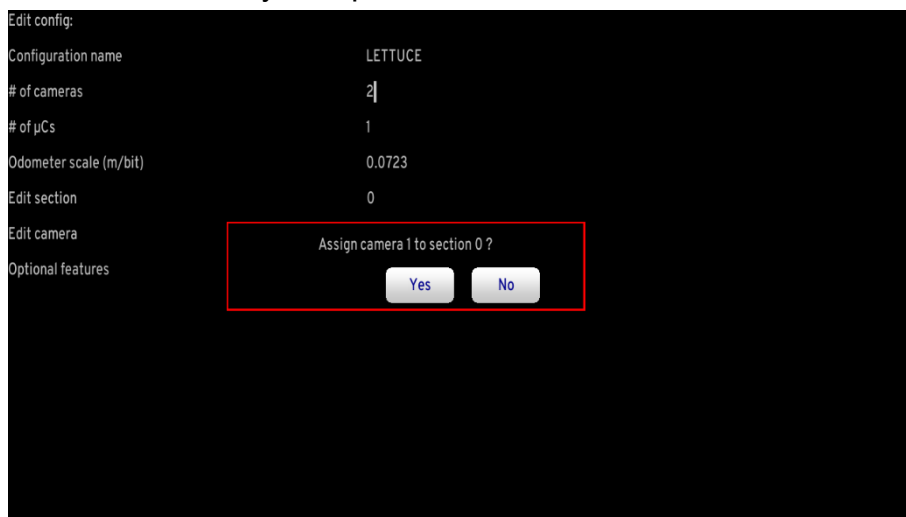
Additional settings available from the advanced editor

Under normal circumstances it should not be necessary to alter any of the additional parameters listed in the advanced editor. However, for those wanting to make more advanced changes they are listed here.

Additional general settings

The advanced version allows the user to change the number of cameras and microcontrollers fitted.

For example, adding an additional camera can be achieved by increasing the number of cameras fitted by one. You will then be asked if you wish to assign this camera to a section for guidance purposes. Normally you would reply “Yes”. If you also wish to copy the setup settings from the previous camera setup you can also reply “Yes” to the next question. However, it is also possible to configure each camera differently if required.



Configuration editor screen with advanced settings selected

It is also possible to add additional cameras that are not used for guidance, but instead provide a CCTV function. To add a camera for this purpose do not allocate that camera to a section. The cameras mounted on the configuration edit section screen remains unchanged. On the edit camera screen relating to the additional camera enter 0 rows and no row spacing. That camera will produce an image on the working screen with no overlaid graphics that can be selected from the thumbnails in the usual way.

Changing of the number of microcontrollers (**# of μCs**) is typically only required if you intend to operate the console in “Demo” mode without connection to an implement, for example at an exhibition.

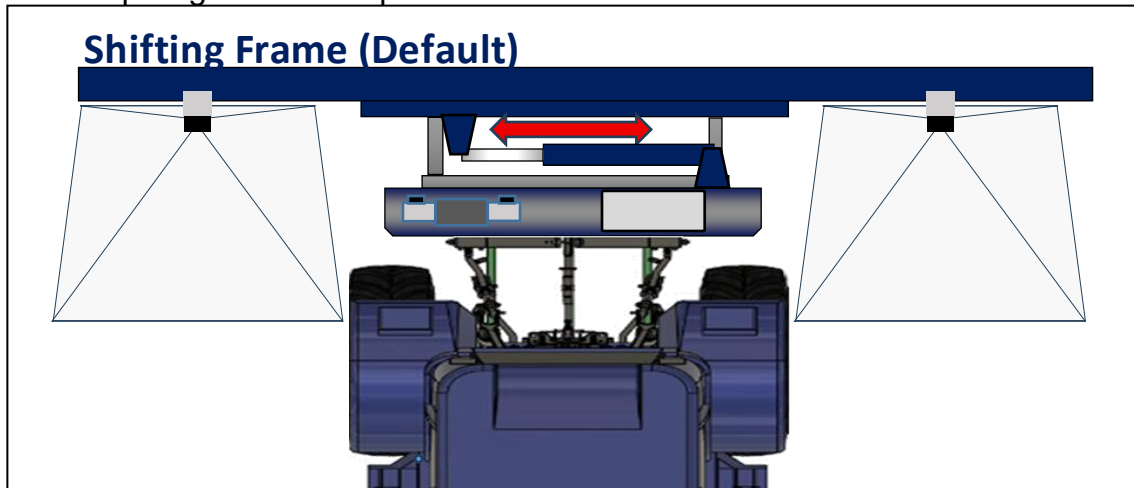
Setting the number of microcontrollers to 0, as well as modifying the **Odometer on μC** and **Steer using μC** settings as described below to blank/none will enable you to operate a console in demo mode from image sequences without connection to an implement. Image sequences can be loaded to the console via the Service Menu, See [Section 11](#).

If you wish to make use of this facility see [Annex](#) and/or [Contact THT](#) for assistance.

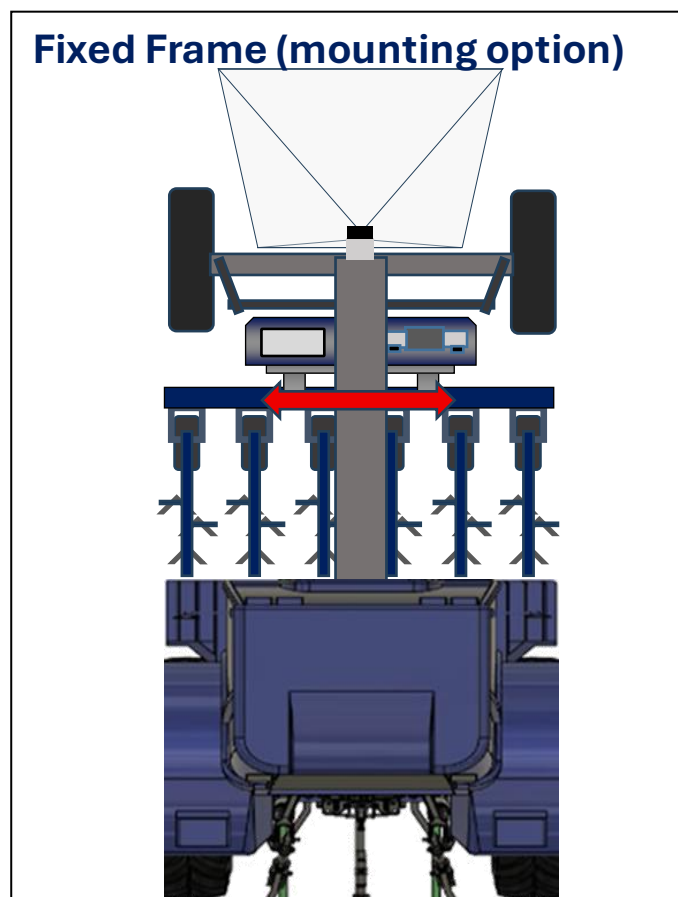
It is not advised to modify this setting unless you are sure of the changes you wish to undertake. Multi-section implements will have # of μCs greater than 1, additional guided sections can be added by making a new multi-section configuration from defaults.

Additional section settings

“**Camera mounting**” relates to how the camera(s) are mounted. The default and best solution used by the majority of machines mounts the camera on the shifting frame so that both cameras and tools are kept aligned with crop rows as illustrated below.



Alternatively, it is also possible to configure systems so that camera(s) can be mounted on a fixed frame that does not move with implement tools. In this case the shifting frame and tools are kept aligned with crop rows, but the camera will stay aligned with the tractor and fixed frame. This configuration is only intended for applications where it is difficult to otherwise provide cameras with an adequate view such as the mid mounted implement illustrated below.



Note: If operating in a fixed frame configuration, side shift position measurement **must** be accurately calibrated.



Configuration editor “Section” screen with advanced settings selected

“**Distance behind rear axle**” is the distance between the cultivators and the tractors rear axle. Note, if the implement is front mounted that figure becomes negative.

The “**Lift input**” determines which microcontroller that section should take its lift input from. For ISOBUS enabled implements there is a menu allowing selection between ISOBUS/front, ISOBUS/rear and microcontroller inputs. Multi-section implements can derive lift inputs for multiple sections from a single input.



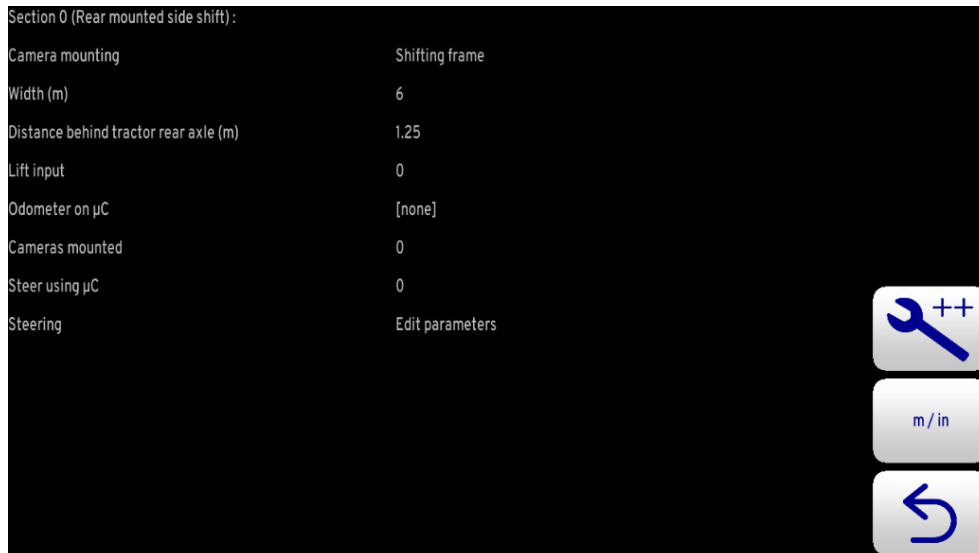
Selection of Lift input source in configuration “Section” advanced editor screen

“**Odometer on μ C**” determines which microcontroller that section should take its odometric speed from. If microcontroller number for the odometer is left blank/”none”, odometric speed will be calculated from the flow of features through successive images.

Note: If ISOBUS speed is selected under standard general settings, the setting for “Odometer on μ C” will not be displayed.

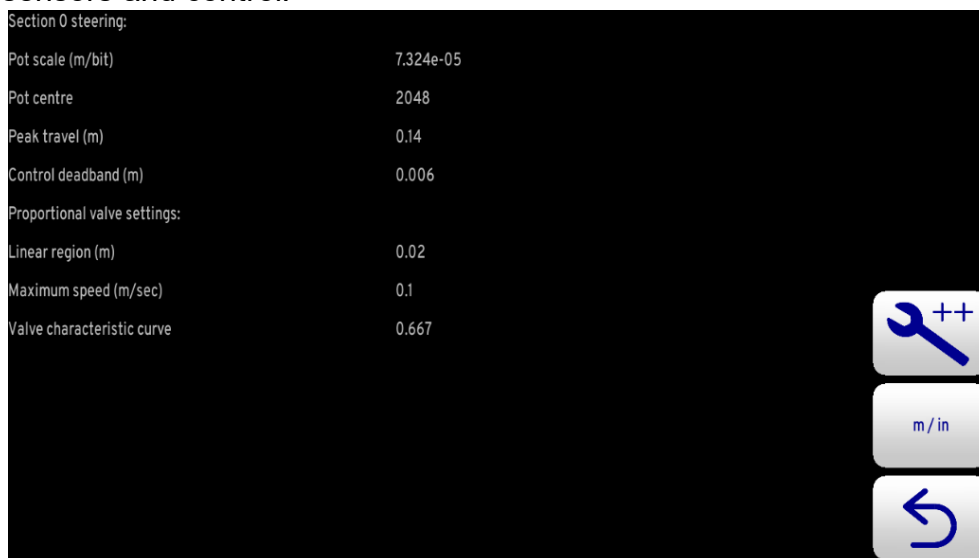
“**Cameras mounted**” listing them by index number with comma delimiting. E.g. a two camera machine might have “Cameras mounted” 0, 1

“**Steer using μ C**” determines which microcontroller that section should use to provide steering control.



Configuration “Section” advanced editor screen for a front mounted side shift implement

Under the final line “**Steering**” if you opt to “**Edit Parameters**” you will get a further page: “**Section (No) steering**” allowing users to alter additional parameters relating to steering mechanisms, sensors and control:



Edit Steering Parameters advanced editor screen for a side shift implement

“**Pot centre**” the value of position sensor reading that is defined as central (normally 2048).

“**Control Deadband (m)**” is the minimum steering error that results in a corrective action. Smaller values increase accuracy but can cause rapid steering oscillations if the steering rate (oil flow) is set too high. As standard this is set to 0.006m. For disc steered machines, deadband is measured in degrees and as standard is set to 0.343775°.

For proportional valves only:

“**Linear region**”, “**Maximum speed (m/sec)**” and “**Valve characteristic curve**” all relate to the control of proportional hydraulic valves. They may need adjustment to suit some proportional valves. Experience shows default values are good base to start from and will work for most valves. Their function is explained by a diagram/graph in the help (?) facility.

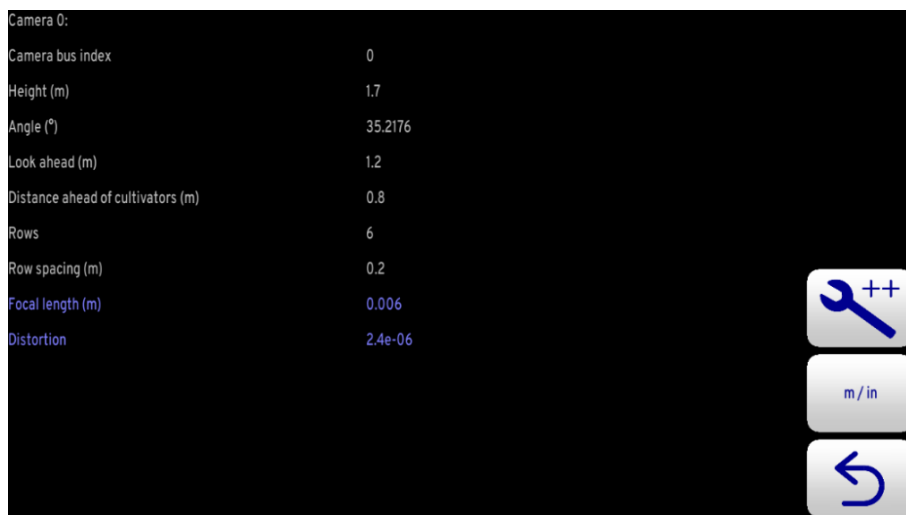
Disc steered machines (not shown in example) can be fitted with an additional potentiometer to display linear free shifting slide position on the working screen light bar. The parameters for this

additional lightbar potentiometer are derived in the same way as you would for a side shifted machine. If the lightbar peak travel is set to zero, the system assumes there is no separate lightbar position sensor, and the working screen light bar will display steering disc angle instead. There is also a damping term that only relates to disc steering.

Additional camera settings

Additional camera parameters are lens focal length and a figure relating to lens distortion correction. However, cameras from serial No 717 onwards have this lens data stored internally, which takes precedence over configuration data, making these figures irrelevant, except where older cameras are fitted.

It is also possible to change camera bus index, though this should not be changed from the camera number in blue above without taking expert advice.

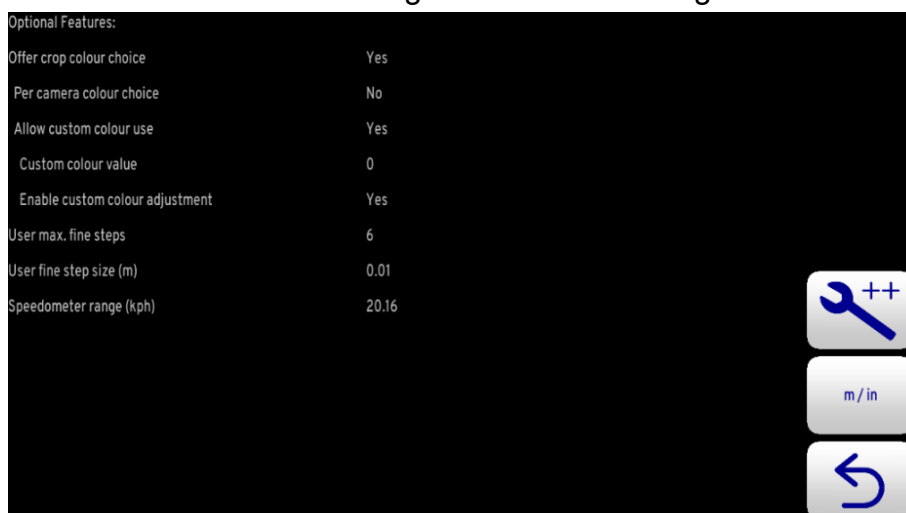


Configuration “Camera” advanced editor screen

Optional Features

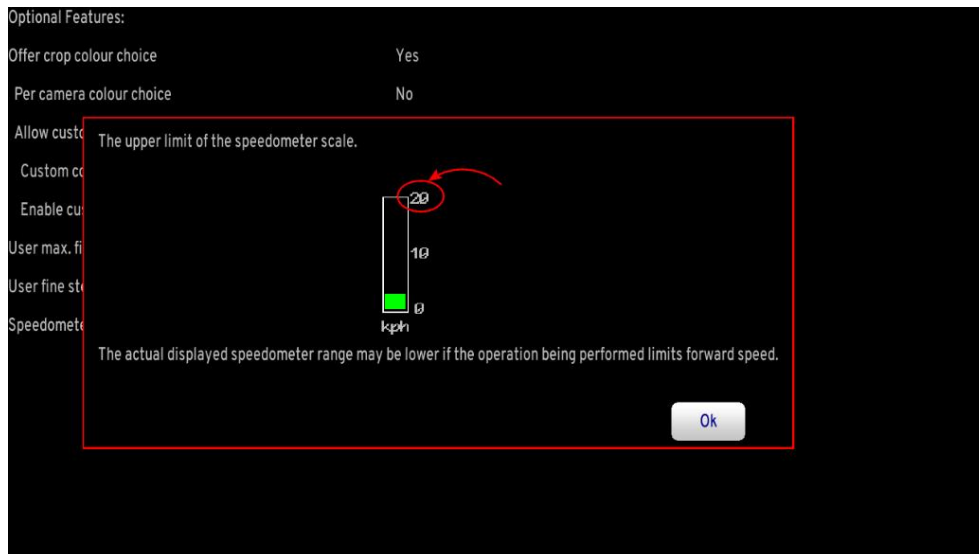
These allow users extra facilities. The **“Offer crop colour choice”** allows users to select crop colour choices other than the standard green via the working screen. As a refinement that choice can be offered per camera with **“Per camera colour choice”**.

To reduce complexity, we recommend only enabling colour choices that are essential for good performance. The default colour choice is between “Green”, “Red” (for red leaved crops) and “R & G” (for crops with a mixture of green and red leaves). A custom colour of fixed hue can be selected as an additional colour choice. A further optional graphical tool can be enabled allowing that custom hue to be varied from the working or advanced settings screen.



Configuration “Optional Features” advanced editor screen

There are two options relate to customising fine offset which can be useful if extra stroke is required working across steep slopes for example. One allows the maximum number of fine offset steps to be changed (default is 6) and the other allows the size of those steps (default 10mm) to be modified. The range of the speed bar displayed on the working screen can be changed from the default 20kph, this is useful for situations where lower working speeds are anticipated, and a more appropriate speedometer range is required.



Example of context sensitive help obtained by touching the red ? touch screen key.

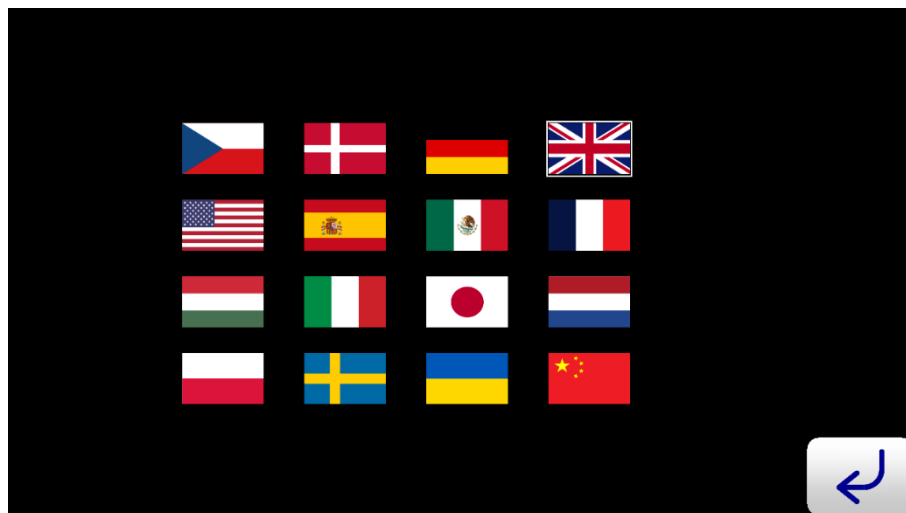
11. Service menu tools (including USB Update and backup procedure)

From the start-up screen users can enter a service menu by touching the tools symbol. The service menu, illustrated below, offers a number of tools and sub menus that can be useful in maintaining or fault finding a system. The QR code defaults to our website but can be configured as part of branding.



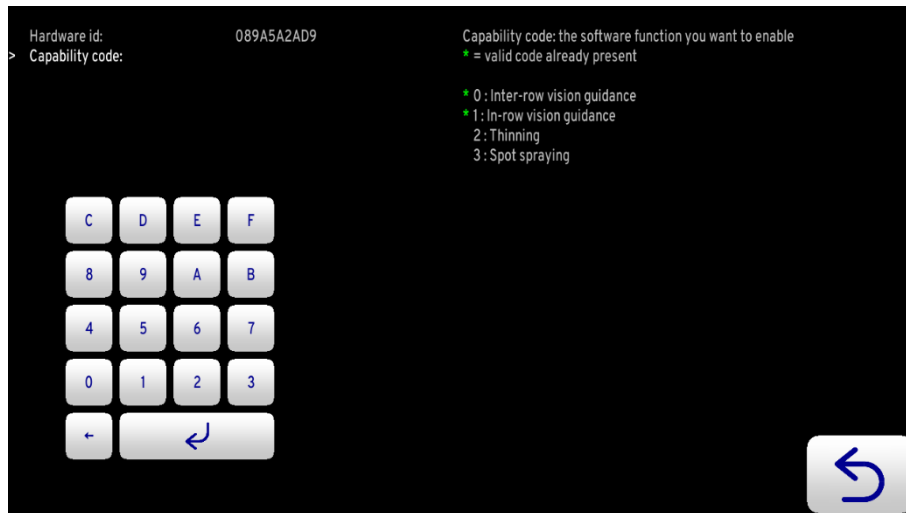
Select language

Selecting this function brings up a screen with an array of national flags. Touching on a flag highlights it with a white border and will change the language to that corresponding to the flag. Where translations are missing, or incomplete, language reverts to English. In practice translations are mostly complete for users screens, but there are significant gaps in most languages for the configuration editor. If you would like to contribute to translations, we would be very pleased to provide you with a translations table.



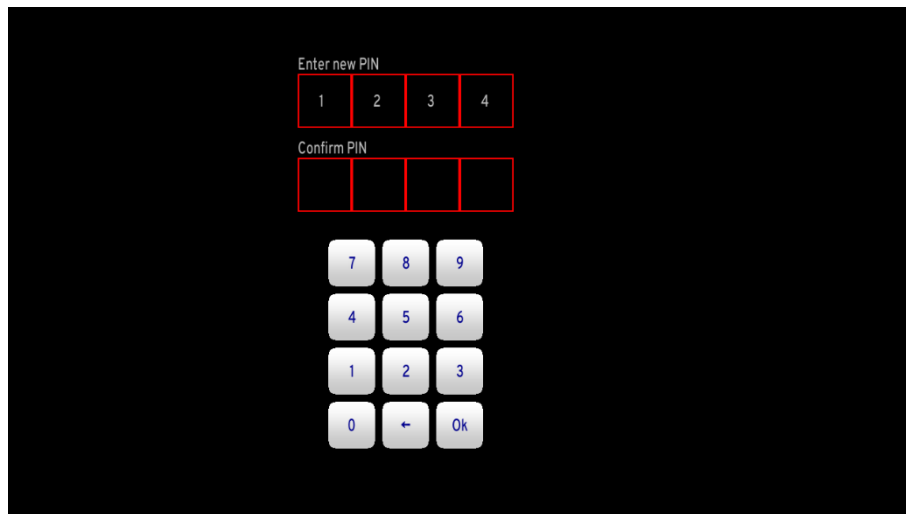
Add product key

This feature allows activation of additional software or functions. Please [contact Tillett and Hague](#) when using this facility with your unique hardware id (shown top left) for your selected console. A unique product key for the console can then be generated by Tillett and Hague and entered to activate the additional capability.



Reset PIN

To reset the PIN the old access code must be entered (factory default = 1,2,3,4). If the old code has been lost contact us for reset instructions.



Capture images to USB device

This function saves still images or short image sequences which can be e-mailed to an expert for analysis. It is a particularly useful tool when used in conjunction with backup as the combined information is helpful for remote fault diagnosis. Still images are in a .tiff format that can be displayed on most computers and are adequate for most diagnostic purposes. Image sequences use a raw data format that can be useful for development.

Ensure that a USB stick is inserted and select the capture function. You will see a screen with a small live video image and touch buttons down the right-hand side. To capture a still image touch on the button with the camera logo. You will hear a buzzer sound and a directory "images_0" will be created on the USB stick and an image "cam0_0.tiff" placed in that directory. You can capture more images with the same camera, and they will be numbered sequentially in the same directory.

To capture short sequences of images touch on the movie camera logo to start recording. Touch again to stop. Normally you only need to record very short (1second) clips.

If multiple cameras are fitted these can be selected using the left and right arrow buttons and images captured from them in the same way and named according to the camera index.



Backup/Restore ->



Backup configuration to USB device

Backup creates a file containing all the parameters stored in all the configurations on a console as well as information such as error logs and camera skews. It can be very helpful in diagnosing faults, restoring systems after hardware failure and as a means of quicky setting up new machines in a factory environment.

To backup to a USB device the memory stick must be inserted into the USB port of the console prior to entering the service menu. If this is not the case, or if the USB device is not formatted in the correct form, you will see a black screen with the message “No USB storage device found”. Similar messages will be received for other operations requiring a USB memory stick.

If the console has a valid USB device connected it will then save a backup of the configuration data to the first directory of the device. The file name being in the format “backup_0.tgz”. If there are already backup files stored on the device the backup will be named numerically one higher than the last backup. Backup files can be copied onto another computer and renamed but names must be in the format backup*.tgz where * can be a string of alphanumeric characters excluding spaces. Ensure that your laptop or computer does not attempt to open/unpack the file as that can corrupt the file into an unreadable format.

Restore configuration from USB

To restore data from a USB device it must be inserted into the USB port of the console prior to entering the service menu.

If no backup files can be found on the USB device or backup files have been corrupted, you will see a black screen with the message “Can’t open backup file”.

If more than one backup is found on a USB device a choice of which backup to restore from is given.

When restoring from a specific backup you are able to choose whether to apply the restoration to only configuration data (“Just Config”) or to all settings such as area meter, hours run, camera skews etc (“All”). In most situations only configuration data will need to be restored from. Restoring files does not delete files already stored in a console. Where configurations are duplicated the old version is overwritten.

Software ->



View installed software

Lists software loaded e.g. inter-row guidance along with version number.

View archived logs

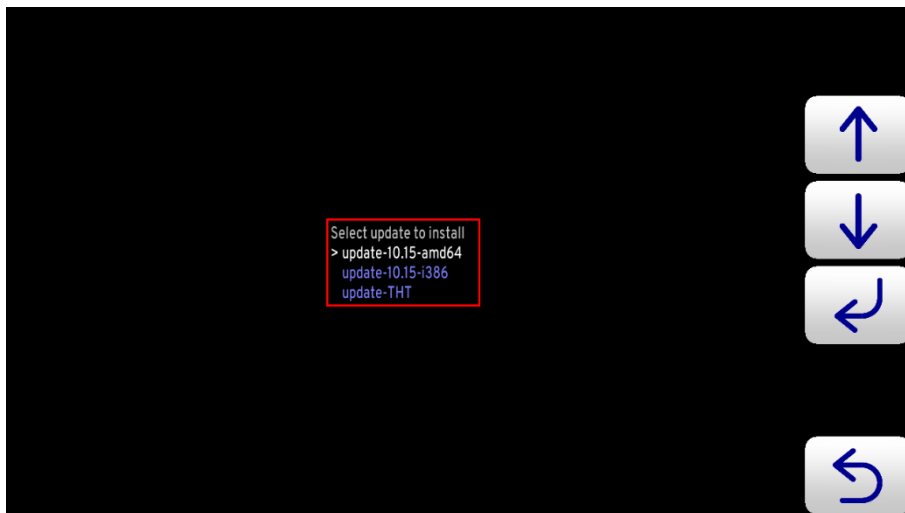
This is a list of one line error messages that have been deleted or overflowed from the error log.

Apply update from USB Device

The update tool updates application software and can therefore be used to keep older machines up to date with the latest features.

It is important that when you are sent an update file of the format update*.tgz you ensure that your laptop/computer does not attempt to open or unpack it as this may cause corruption. When wishing to apply an update to a console it is recommended to copy and paste this file into the top directory of your USB device.

If multiple updates are stored on your USB device, you will be given a menu to decide which update you would like to select and install onto the console.

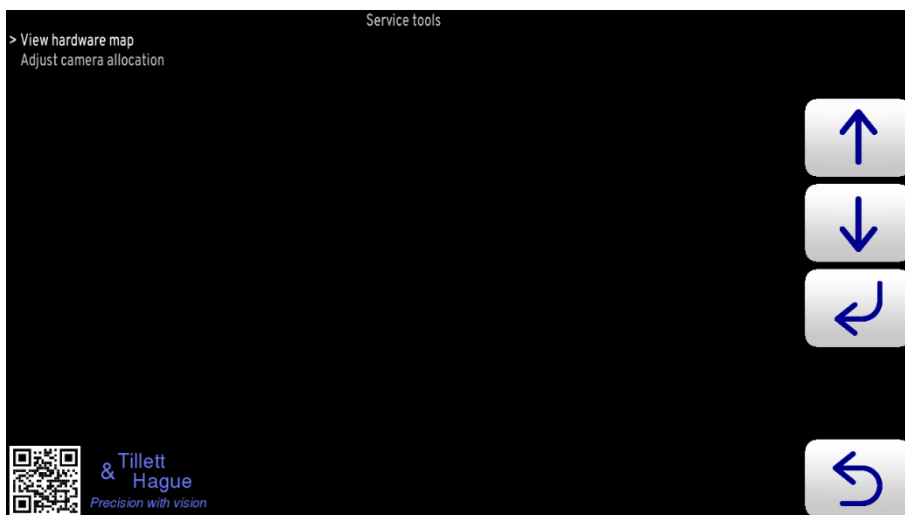


Once your update has been successfully installed you will see a black screen with the message: "Installing update, Done"

Remove software (with caution!!)

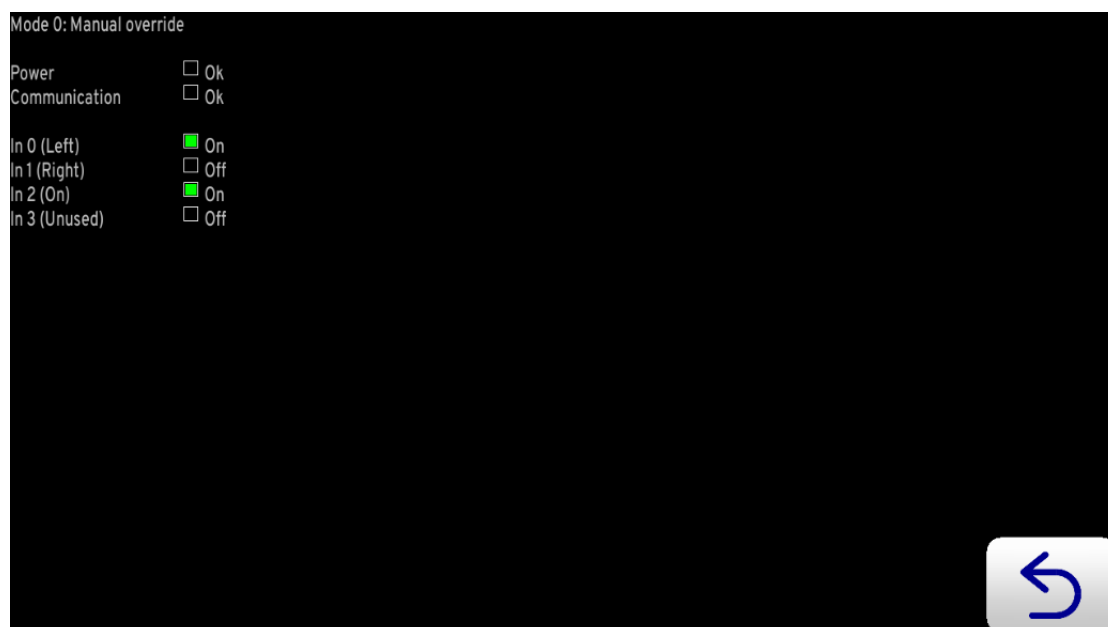
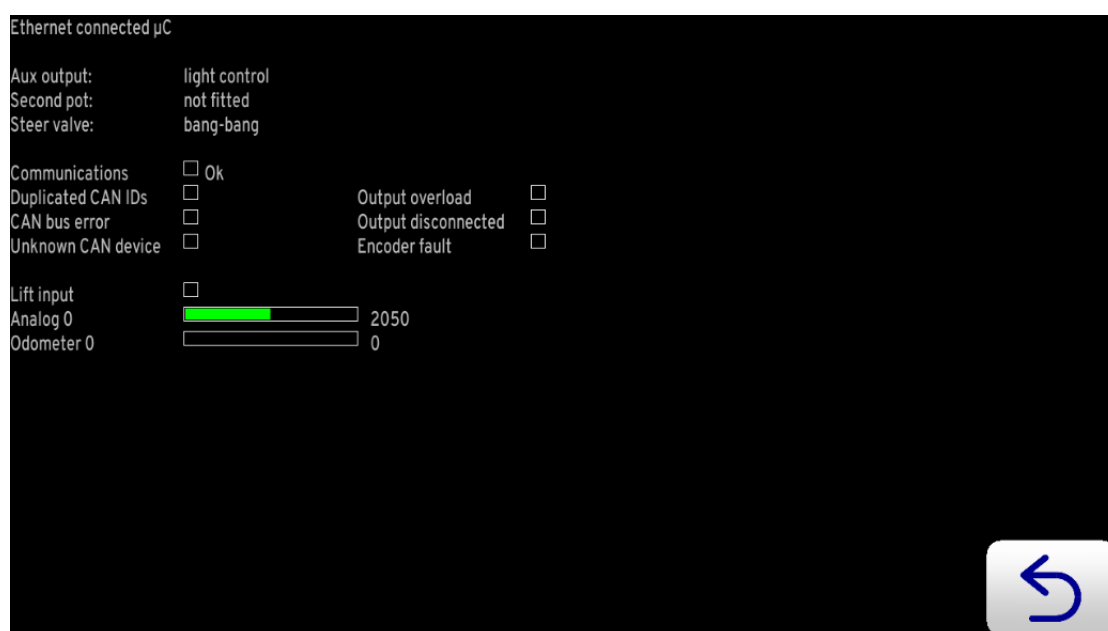
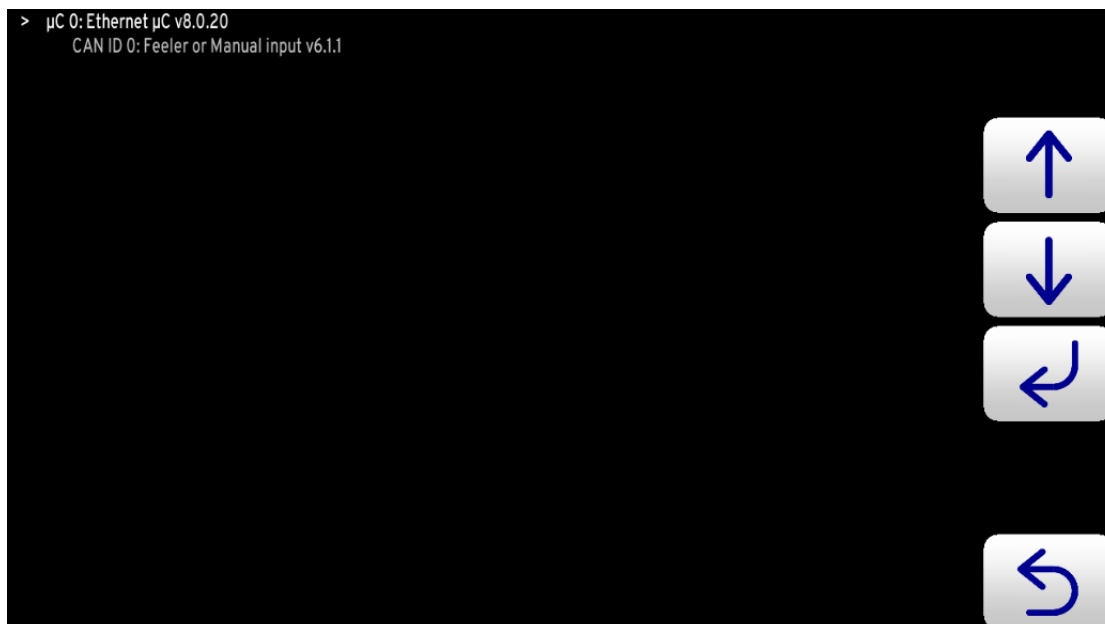
This is a function for removing unwanted modes of operation e.g. after selling a demonstration system you may wish to remove demo mode. However, it is very rarely required and should never be selected unless you are absolutely sure you want to delete software permanently.

Hardware management ->



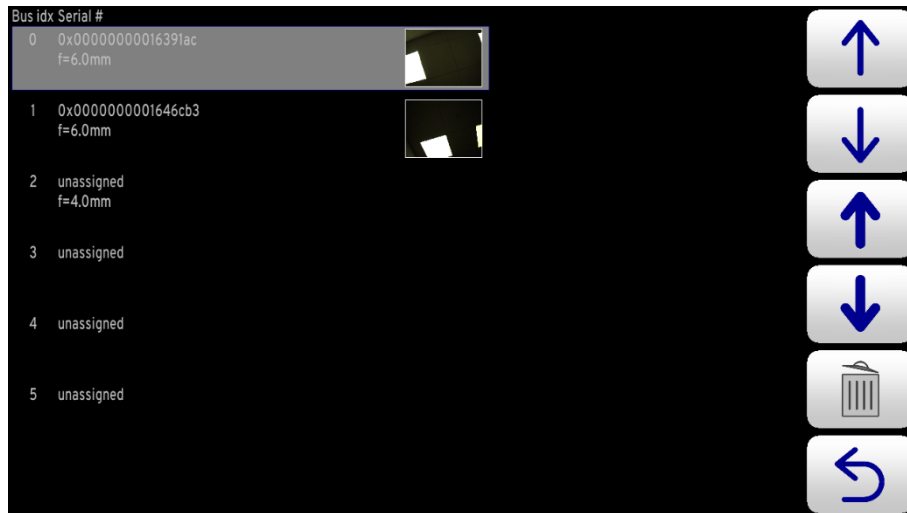
View hardware map

This tool lists all connected microcontroller boards and accessory CAN devices. The address IDs for each connected component can also be viewed to ensure that the address you have intended for each component is correct. This is only necessary when dealing with multi-section machines or machines with multiple CAN devices added. Use the arrow keys to select a board (the text turns from blue to white) and then touch the return button to get live board information such as setup information, communication status and input and output values.



Adjust camera allocation

This tool adjusts the order in which cameras appear on the working screen so that for example the left-hand thumbnail corresponds to the camera on the left of the implement. Alternatively, cameras can be swapped mechanically.



Camera order from top to bottom in the tool relates to the order in which cameras will be displayed in the working screen from left to right. The tool displays bus index, camera serial number, lens type and a live image thumbnail for camera identification.

Thin arrow buttons on the right-hand side are used to select the camera that you wish to rearrange. Thick arrows adjust the order of the selected camera.

The bin symbol allows for the selected camera to be deleted from the list.

Image sequence management -> (Only displayed if demo mode installed)

[Contact Tillett and Hague](#) Technology if you wish run demo mode see [Annex](#) for details. This is only likely to be necessary for exhibitions and shows that do not permit conventional running.



Install image sequence from USB device

This tool installs image sequence files (.isc.tgz) onto the console's internal hard drive. The utility will check the validity of the sequence and that sufficient hard drive space is available. Following these checks, the sequence will be extracted and installed. Note that this process can potentially take quite some time,

```

INSTALLING IMAGE SEQUENCE CONTAINER (ISC)

Source isc.tgz file:
/mnt/usb/Generic-GreenCabbage0.15m-3Cam9RowEmerg95pct-ModerateWeeds-StraightPath2kph-MiddayOvercast_v1.isc.tgz

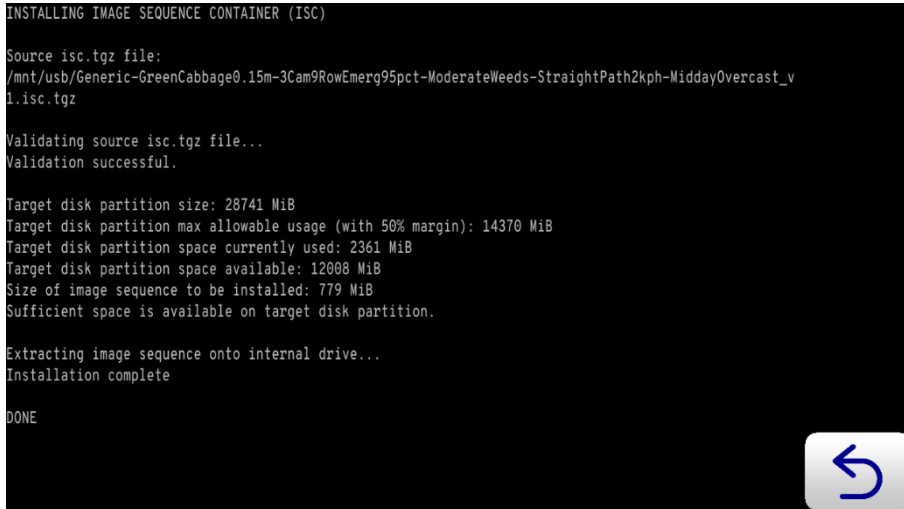
Validating source isc.tgz file...
Validation successful.

Target disk partition size: 28741 MiB
Target disk partition max allowable usage (with 50% margin): 14370 MiB
Target disk partition space currently used: 2361 MiB
Target disk partition space available: 12008 MiB
Size of image sequence to be installed: 779 MiB
Sufficient space is available on target disk partition.

Extracting image sequence onto internal drive...
Installation complete

DONE

```



View details of image sequence

This tool displays field parameters relating to the crop type, crop dimensions, and weed density at the top of the page. Camera parameters, frame rate, resolution, and lens type, as well as camera height and forward angles, are displayed in the middle of the screen. This information can be used to generate configuration files relevant to the image sequences. Note that camera forward angle will need to be converted to a lookahead figure for entry into the configuration editor.

```

IMAGE SEQUENCE CONTAINER (ISC) INFORMATION

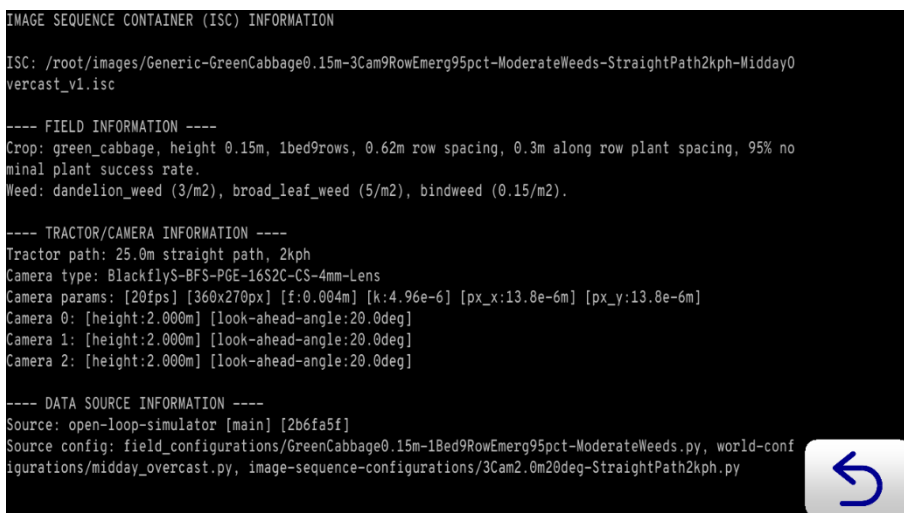
ISC: /root/images/Generic-GreenCabbage0.15m-3Cam9RowEmerg95pct-ModerateWeeds-StraightPath2kph-MiddayOvercast_v1.isc

---- FIELD INFORMATION ----
Crop: green_cabbage, height 0.15m, 1bed9rows, 0.62m row spacing, 0.3m along row plant spacing, 95% minimal plant success rate.
Weed: dandelion_weed (3/m2), broad_leaf_weed (5/m2), bindweed (0.15/m2).

---- TRACTOR/CAMERA INFORMATION ----
Tractor path: 25.0m straight path, 2kph
Camera type: BlackflyS-BFS-PGE-16S2C-CS-4mm-Lens
Camera params: [20fps] [360x270px] [f:0.004m] [k:4.96e-6] [px_x:13.8e-6m] [px_y:13.8e-6m]
Camera 0: [height:2.000m] [look-ahead-angle:20.0deg]
Camera 1: [height:2.000m] [look-ahead-angle:20.0deg]
Camera 2: [height:2.000m] [look-ahead-angle:20.0deg]

---- DATA SOURCE INFORMATION ----
Source: open-loop-simulator [main] [2b6fa5f]
Source config: field_configurations/GreenCabbage0.15m-1Bed9RowEmerg95pct-ModerateWeeds.py, world_configurations/midday_overcast.py, image-sequence-configurations/3Cam2.0m20deg-StraightPath2kph.py

```



Remove image sequence

This tool can be used to remove image sequence files from the console's internal hard drive.

12. Maintenance and Storage

Please follow the maintenance and storage instructions below in order to ensure your precision guidance system stays in first class working order.

1. Regularly check the routing of hoses and cables and protect against chaffing.
2. Although all components are designed to be shower proof we recommend that the console is housed in a dry environment and that the implement is not exposed to wet weather for extended periods when not in use.
3. Always ensure power is supplied from a supply that is appropriately fused (10 - 20 amp).
4. Always ensure the correct supply polarity is adhered to.
BLUE = - negative, **BROWN** (fused side) = + positive.

13. Trouble shooting

LED blink codes

As an aid to fault finding most system components are fitted with LEDs whose mode of illumination can provide information on system status and any error conditions.

Console front panel button LED

Under normal conditions with 12V power connected via the implement module, but with the console switched off the front panel LED gives a very brief single blink at 5 second intervals. When switched on and running normally the LED is illuminated continuously.

Other patterns of illumination indicate error conditions that use the following codes:

- Single 0.2 s blink followed by 1 s off indicates The ITX board has failed to start up
- Two, three or four 0.2 s blinks followed by 1 s off indicate different touch screen errors.

Implement module

The implement module has a green LED fitted near the power lead entry gland. It is not illuminated at all when the system is powered down. For about 10 s on initial start-up it is continuously on indicating that it is waiting for CAN devices to register. It will then normally go into a period of slow blinks (1.6 s on 1.6 s off) on a continuous cycle indicating that the system is ready, but idle, with no demands coming from the console via Ethernet. This state will continue until the working screen is displayed and crop row tracking has commenced. Once demands are received from the console a rapid (0.2 s on 0.2 s off) continuous blink cycle starts indicating Ethernet data is being transferred. The LED will revert to a slow blink on entry to the set up screens or configuration editor.

Other patterns of illumination indicate error conditions that use the following codes:

- Single 0.2 s blink followed by 1 s off indicates 2 devices found with the same CAN address
- Two 0.2 s blinks (i.e. 0.2s on 0.2s off 0.2s on) followed by 1 s off indicates too many CAN errors to operate
- Three 0.2 s blinks followed by 1 s off indicates a component is connected that does not conform to known types.
- Four 0.2 s blinks followed by 1 s off indicates the valve over current trip is active, possibly due to steer valve output short circuit
- Five 0.2 s blinks followed by 1 s off indicates open circuit on a steer valve output

Manual and Feeler modules

Both these modules contain a microcontroller board that has one green LED and four red LEDs that can be viewed by removing the lid.

The green LED is continuously illuminated in an idle state and flashes 50% on 50% off at 2Hz when running normally. It blinks briefly at 2Hz if the power supply to the proximity detectors is short circuit.

The red LEDs are illuminated with their corresponding inputs.

ISOBUS CAN interface PCB

The ISOBUS CAN interface board has two LEDs to indicate power and status. When operational LED1 should be illuminated continuously. In the event of a fault this LED will produce the following error codes:

- Two 0.2 s blinks (i.e. 0.2s on 0.2s off 0.2s on) followed by 1 s off indicates invalid configuration, check mode DIP switches located on other side of PCB.
- Three 0.2 s blinks followed by 1 s off indicates an internal error (contact THT)
- Four 0.2 s blinks followed by 1 s off indicates an ethernet failure, power off and check ethernet connection between PCB and Ethernet switch and then retry.
- Five 0.2 s blinks followed by 1 s off indicates a CAN failure, power off and check ISOBUS cabling and CAN connections and then retry.

LED2 should illuminate continuously when ECU Power is available. If LED2 is not illuminated, power off and check connections.

Fault codes (as displayed in error messages and the error log)

These numeric fault codes can provide more specific information than the written description displayed on the screen. Make a note of these codes when reporting errors.

ctnnn c=class, tt= 2 digit type, nn= channel/index

0xxxx internal software error codes

00100 state/covariance dimension error
 00200 variance sign error
 00300 other numeric error

1xxxx camera error codes

101xx excess skew
 10300 no port found
 10400 no devices at all
 10500 just the adaptor
 106xx some devices, but no cameras found
 107xx Unsupported camera
 108xx Initialisation failure
 109xx can't start capture
 110xx can't start video transmission
 111xx can't work out GUID assignments
 112xx Timeout on a particular camera
 11300 no data from ANY camera
 11400 camera connection too slow

2xxxx Implement module uc error codes

201xx the device you want is not found
 202xx timeout on data receive
 203xx timeout on diag receive
 204xx missing sync in packet
 205xx checksum wrong
 206xx received data packet not what we asked for
 207xx other data format error
 20800 no uCs at all
 209xx Excessive number of CAN bus errors
 210xx More than one device set to same ID
 211xx Unrecognised CAN device
 212xx Valve output overload

3xxxx Rotor error codes

301xx No rotors present
 302xx Rotor index sensor fault
 303xx Rotor overheat RHS
 304xx Rotor overheat LHS
 305xx Overheat - rotor CPU
 306xx Rotor overload
 307xx Rotor Hall effect sensor fault
 308xx Tractor (12V) battery voltage low
 309xx Rotor overload in braking.

310xx Rotor CPU timeout (Should not be seen)

311xx Lost sync, +12V power interruption?

4xxxx Other hardware error codes

40100 Odometer consistently seems wrong

40200 Pot error

40300 CPU fan alarm

40400 CPU Thermal alarm

5xxxx Operator errors

50100 Going too fast!

6xxxx Condition monitoring errors

60100 Sensor/wiring short circuit

60200 Hydraulic pressure low

60300 Hydraulic tank return pressure high

60400 Reverse oil flow

60500 Hydraulic overheat (>70C)

60600 Hydraulic filter blocked

7xxxx Spray system faults

70100 Spray pressure low

70200 No flow detected

70300 Leakage detected

70400 Missing pressure sensor / wiring fault

70500 Nozzle blocked

8xxxx Actuator board errors

80100 Low valve supply voltage

80200 Output overload

80300 Valve not connected

9xxxx CAN connect errors

90100 Can't load dll

90200 Missing symbols in dll

90300 Can't communicate with CAN bridge

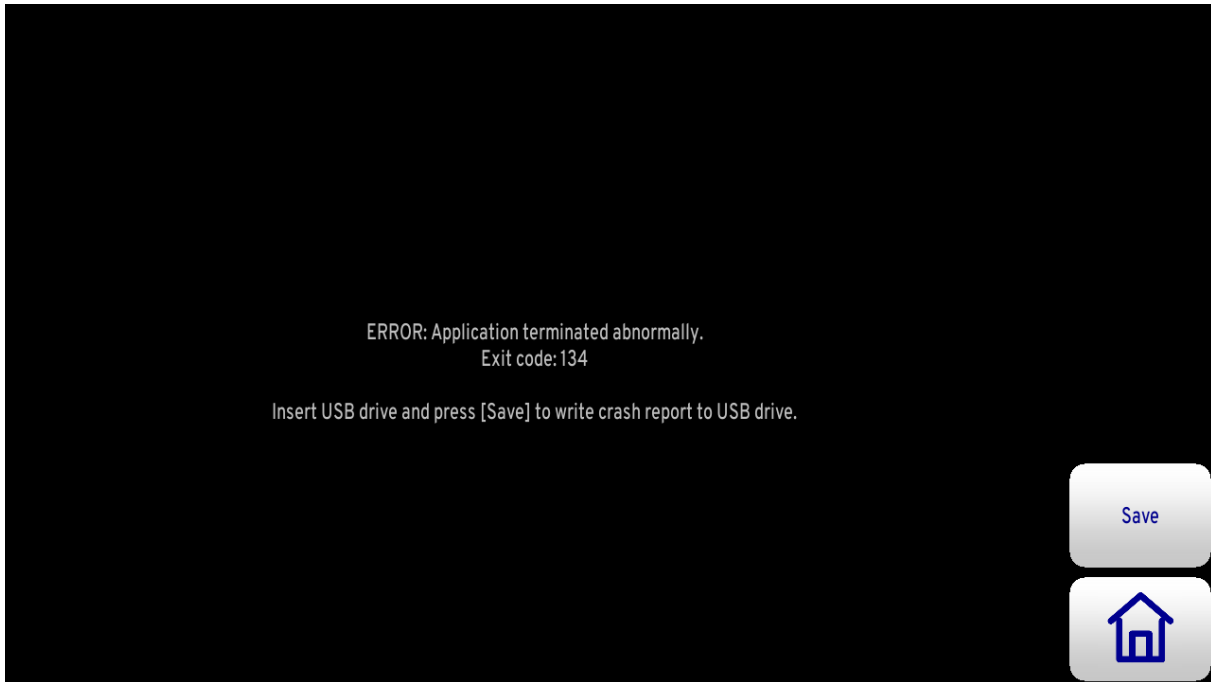
90400 Firmware file missing

90500 Error in firmware (.ihx) file

90600 Flash write failed

Exit Codes and Crash logs

In the event of a critical system error the console will provide an exit code and the opportunity to save a crash log to USB device. If an unknown issue persists that cannot be diagnosed, it is best to take note of the exit code and [contact THT](#) sending the console backup file and the crash log for remote diagnosis.

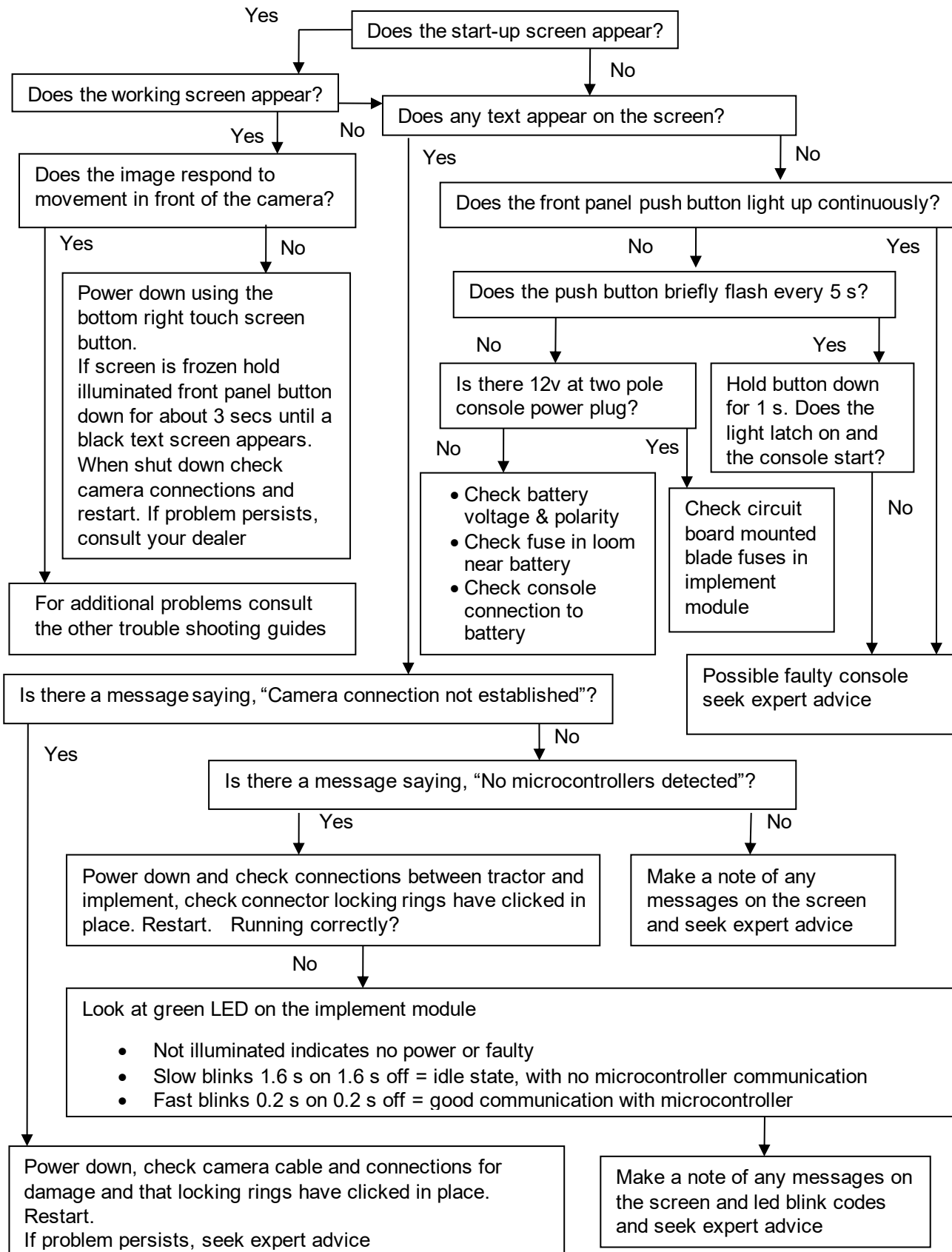


Flow Charts

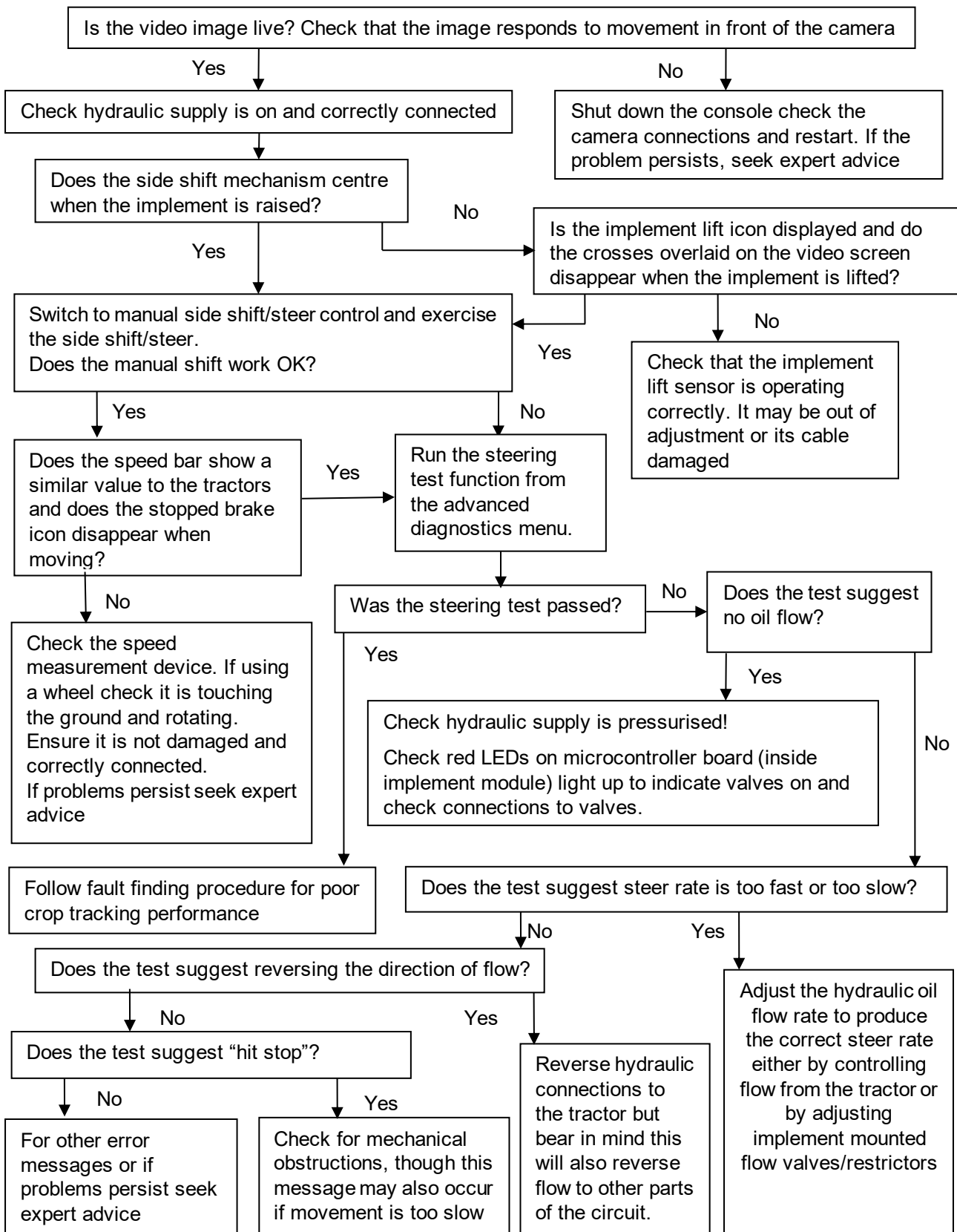
Problems have been divided into three categories listed below:

1. Console fails to start up correctly
2. Console shows a working screen, but the side shift/steered discs do not respond
3. All systems appear to be functioning, but crop tracking performance is poor

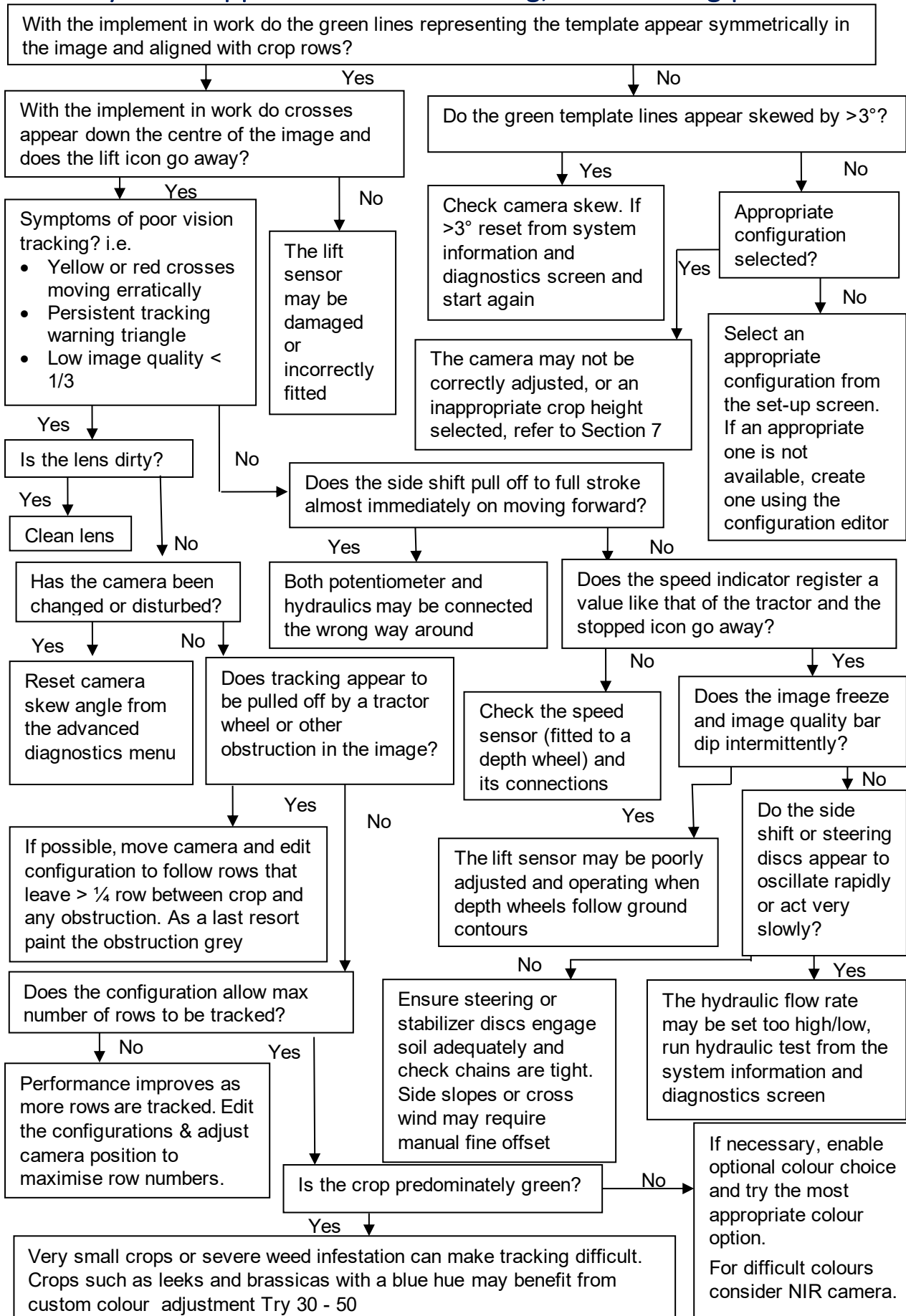
1. Console fails to start up correctly



2. Console shows a working screen, but the side shift/steered discs do not respond.



3. All systems appear to be functioning, but tracking performance is poor



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Annex – Demo mode

Any console can be updated to have a demo mode option. It is intended for use by manufacturers and dealers wishing to demonstrate system capabilities without the need to run in a field. To avoid confusion, we recommend removing demo mode before selling it for general farm use.

Demo mode updates are available on request and are installed by following the standard procedure from the “Software” service tools. Demo mode can be removed using the same tools.

Demo mode also requires the installation of synthetic image sequences to replace images that would normally come from a camera. Image sequence files are available on request for a range of crops and growth stages. They can be created with various motion with respect to crop rows, e.g. a sinusoidal oscillation or straight line. They are installed from a USB stick using the “Image sequence management” service tool, see [Section 11](#). These image sequence files contain meta data providing some configuration parameters relevant to that sequence, e.g. camera lens parameters.

Once a Demo mode update has been applied and at least one image sequence loaded, you will, on starting guidance, be offered the choice “Run” or “Demo”. Selecting “Run” starts standard camera-based vision guidance that will work in the field in the normal way.

On selecting “Demo” you will be asked which of the installed image sequences you wish to run. Once a sequence is selected you will go straight into a working screen with the image sequence running in a continuous loop.

In demo mode all software features including Auto learning operate in the normal way. It is normally satisfactory to use visual odometry for speed estimation.

Configurations can be created to match image sequences in the usual way. If you want to be able to run without connecting to an implement, or do not wish the steering mechanism to move you should, with advanced settings selected, from the top page edit the number of microcontrollers (“# of μC ”) to be zero. You should also under [“Section” settings](#) to set “Steer using μC ” to “none”.

If you do want the system to respond to sensor inputs and to move in response to crop row lateral movement in the image sequence, you need to select a configuration using “Fixed Camera” settings and to select the appropriate microcontroller under [“Section” settings](#). The implements lift sensor will act in the normal way. So, if you want to stop guiding on the image sequence, activate the lift input to the out of work position.

Hydraulic systems

The hydraulic system required to operate a side shift or disc steer system is conceptually a simple one involving a single directional control valve to meter hydraulic oil into either side of a hydraulic cylinder. However, there is often a need for additional components to control the rate of oil flow such as variable restrictors and pressure regulators.

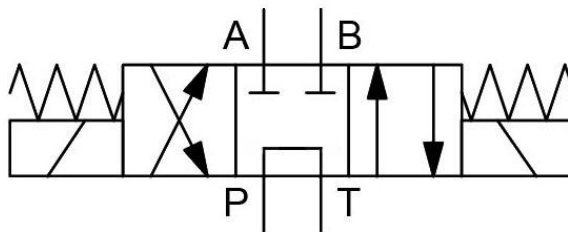
A diverse range of tractor hydraulic power systems introduces further considerations when designing implement hydraulics.

This note is not intended as a comprehensive design tutorial, rather it is a guide to the more common arrangements and a discussion of some of the issues.

It is usually cost effective for implement manufacturers to provide their own hydraulic systems suited to their own requirements. However, if required Tillet and Hague technology can supply basic hydraulic systems as part of a complete guidance and control package.

We will start by considering tractor hydraulic PTO systems. These can broadly be categorised as “open centre” or “closed centre/load sensing”. Open centre systems are generally found on older, or budget tractors, where the oil is supplied from a gear pump at a rate that is proportional only to engine RPM. For these systems an “open centre” directional control valve is preferred in which its centre position provides an unobstructed return path for the oil back to the tank.

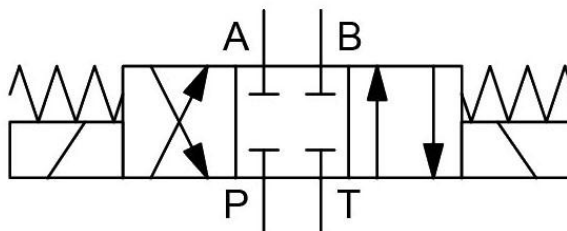
Open centre valve



If a “closed centre valve is used in which the ports are closed in the central position, then oil will be forced to return to the tank via a pressure relieve valve (the tractors own valve is normally set just above 200 bar). This is inefficient and can create large amounts of heat which may damage both tractor and implement.

Tractors with some type of load sensing system maintain a low pressure on standby and only develop full system pressure when flow is detected. These systems can use “closed centre valves”, where the pressure line is blocked in the valves centre position.

Closed centre valve



One advantage of closed centre valves is that it is possible to put additional valves in parallel on the same hydraulic circuit. This can be useful when the implement also features automatic levelling, or tine raising, but it is inconvenient, to supply each of these services from its own independent tractor spool.

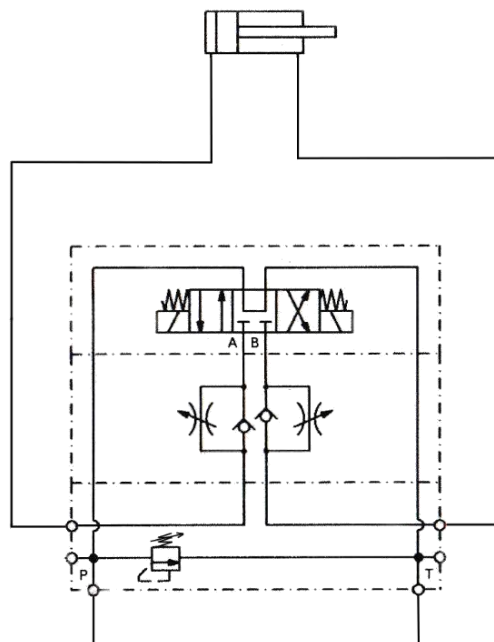
It is also possible to operate multiple closed centre valves with a tractor equipped only with a gear pump and no load sensing, but it requires an additional dump valve. That valve is arranged to be normally open so that tractor oil is returned to tank with little pressure drop when none of the

valves are operated. The dump valve must be wired in such a way that it closes when any of the other control valve operates, leaving them with full system pressure and flow. Tillett and Hague can provide a circuit board with multiple optically isolated inputs which are logically “OR”ed to a dump valve output for this purpose.

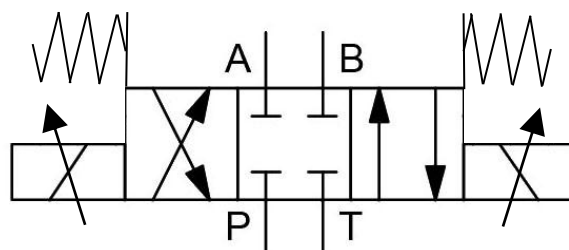
In some tractors it is possible to regulate the maximum flow on each spool independently. Exceptionally this may be sufficient to control the rate at which the steering cylinder moves to the desired target of approximately 0.1m/s. However, because the steering cylinders are normally small in diameter, the required volumetric rate is lower than the minimum offered by the tractor. Furthermore, the two sides of the steering cylinder often have different areas requiring different flow rates in each direction to achieve the same linear speed. To regulate steering rate, it is normal to fit variable restrictors on the output to each side of the cylinder.

It is not uncommon for variable restrictors to be almost fully closed to achieve the required steering rate. This makes setting very sensitive to small adjustments and to oil temperature. It can be advantageous to reduce the pressure across the restrictors with a pressure regulator, enabling them to operate with larger orifices thus reducing their sensitivity. This also has the effect of reducing the force generated by the steering cylinder, which is not normally a problem as steering forces need not be high.

A typical circuit, as provided in the Tillett and Hague standard directional valve block assembly, is given below showing how all these components might be used in a hydraulic circuit.

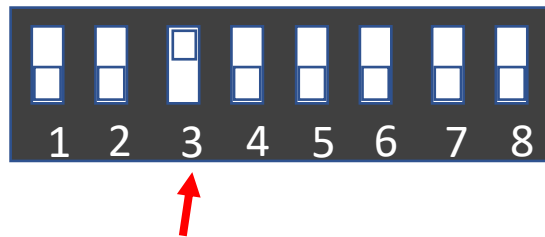


Proportional closed centre valve

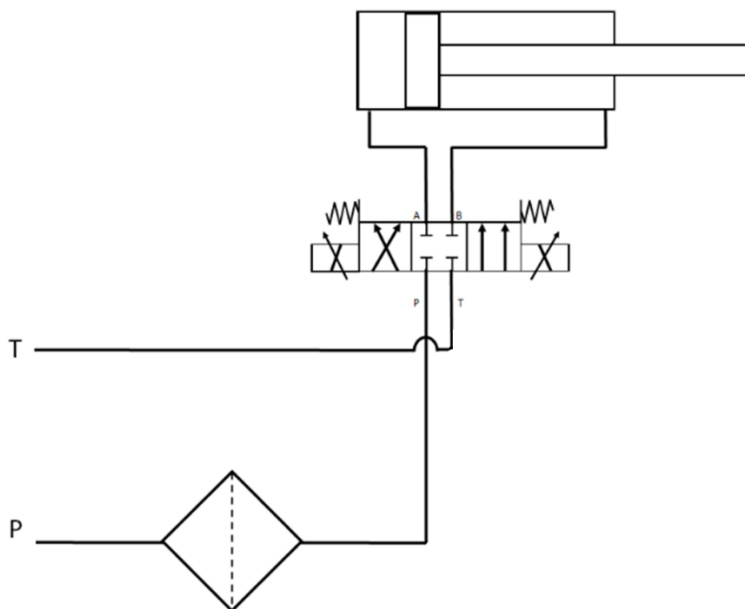


Proportional steering requires a closed centre circuit design. The fine internal tolerances of proportional control valves require a pressure line filter to protect against valve damage. To

activate proportional control option of a proportional control capable implement module DIP switch number 3 must be switched UP to the ON position, as shown below:



Control system parameters relating to proportional control can be found in the configuration editor in [Section 10](#). Valve characteristic curve parameter may need to be adjusted to suit chosen valve. A typical circuit for the Tillett and Hague proportional directional valve block is shown below.



If the tractor hydraulic system allows, reduce the oil flow from the tractor to an appropriate level. 10% of maximum flow is usually sufficient.

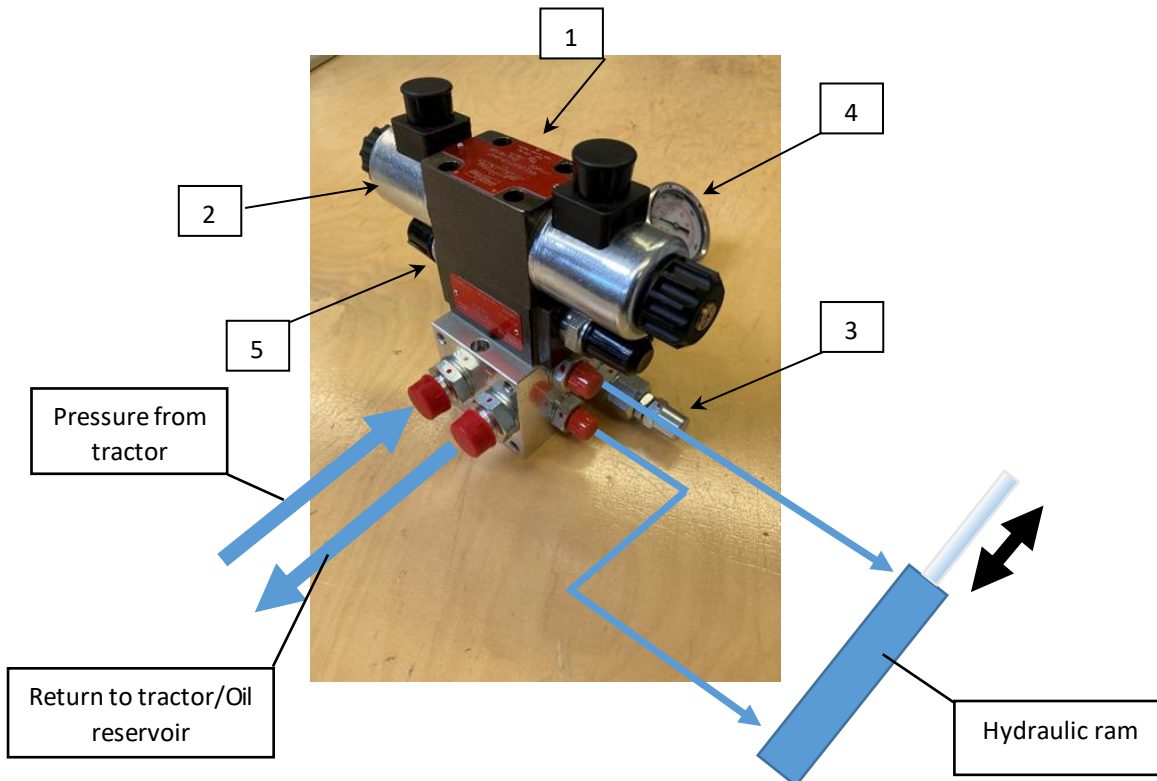
Standard directional control valve setup:

Connect the test point pressure gauge and, after checking that the hydraulic cylinder is safe to operate, turn on the tractor oil supply. The pressure gauge should read zero as the oil is passing unrestricted through the open centre directional valve. Arrange for the directional valve to operate so that the cylinder moves fully to one end of its stroke. The pressure should increase to the value set by the pressure reducer. 20 to 40 bar is normally sufficient. If required, this can be adjusted by loosening the 17mm locking nut and making the adjustment with a 4mm Allen key. If you are using the control system to operate the valve it will switch off once the desired position has been reached, so you may need an assistant to view the pressure gauge whilst the valve is operated, and the cylinder is moving.

If you reverse the direction of operation of the directional valve the cylinder will move to the other end of its stroke. Use the corresponding flow control (needle) valve knob to control the rate of movement. A speed of 0.1m/s is normally a satisfactory starting point but can be adjusted later.

Keep reversing the direction of flow and adjusting the two flow control knobs until speed is satisfactory in both directions. If you find that the flow control adjustment is too sensitive, you can try further reducing operating pressure using the pressure reducing valve.

Once you are happy with the pressure you can remove the test point gauge.

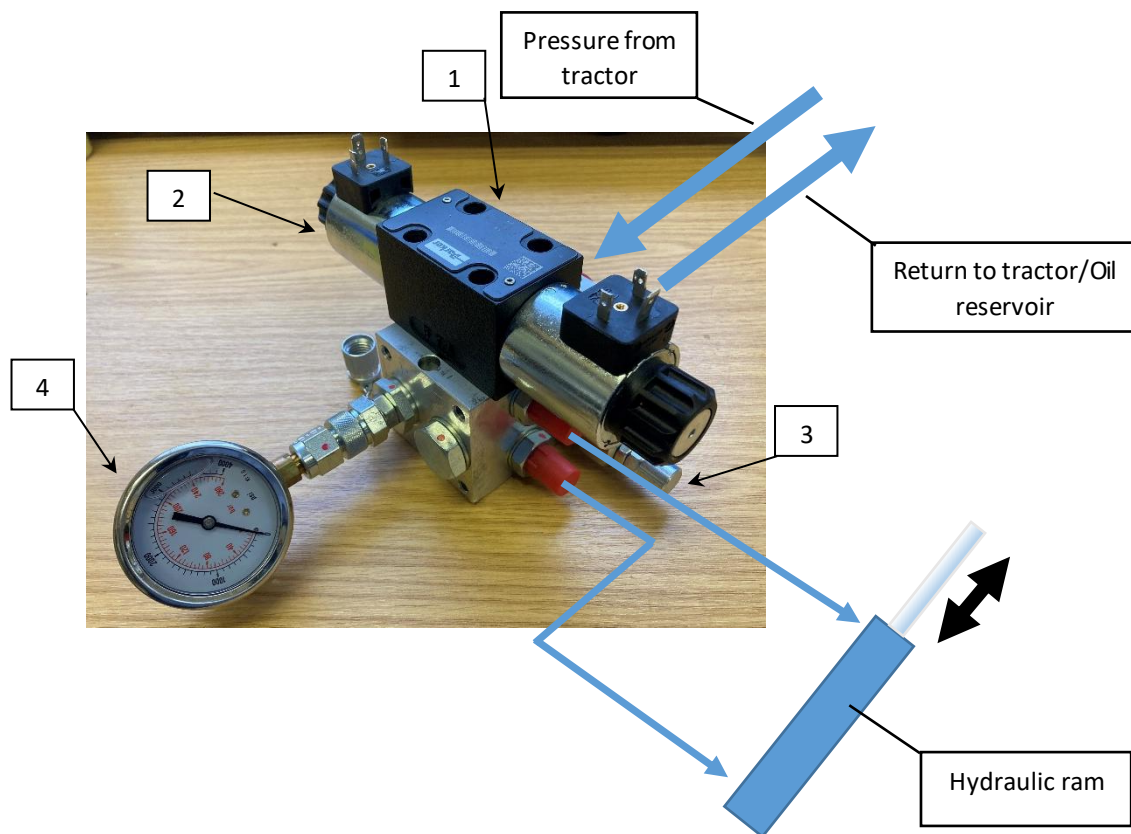


	Part Name	Part Function
1	Directional control valve	Open centre directional control valve used for diverting flow of oil
2	12V solenoid coil	Activates valve to direct oil flow
3	Pressure Reducer adjuster and locking nut	Used to set operating pressure
4	Test point gauge	Used to measure operating pressure, (only required for setup and not routine running)
5	Flow control valve	Used for setting flow rate to left and right steering functions independently

Proportional hydraulic system setup:

After checking that the hydraulic cylinder is safe to operate, turn on the tractor oil supply. Use the test steering application located in the advanced settings and diagnostics screen to test and calibrate the proportional control circuit.

Peak cylinder speed can be increased or decreased in the configuration editor, as standard this is set to 0.1m/s



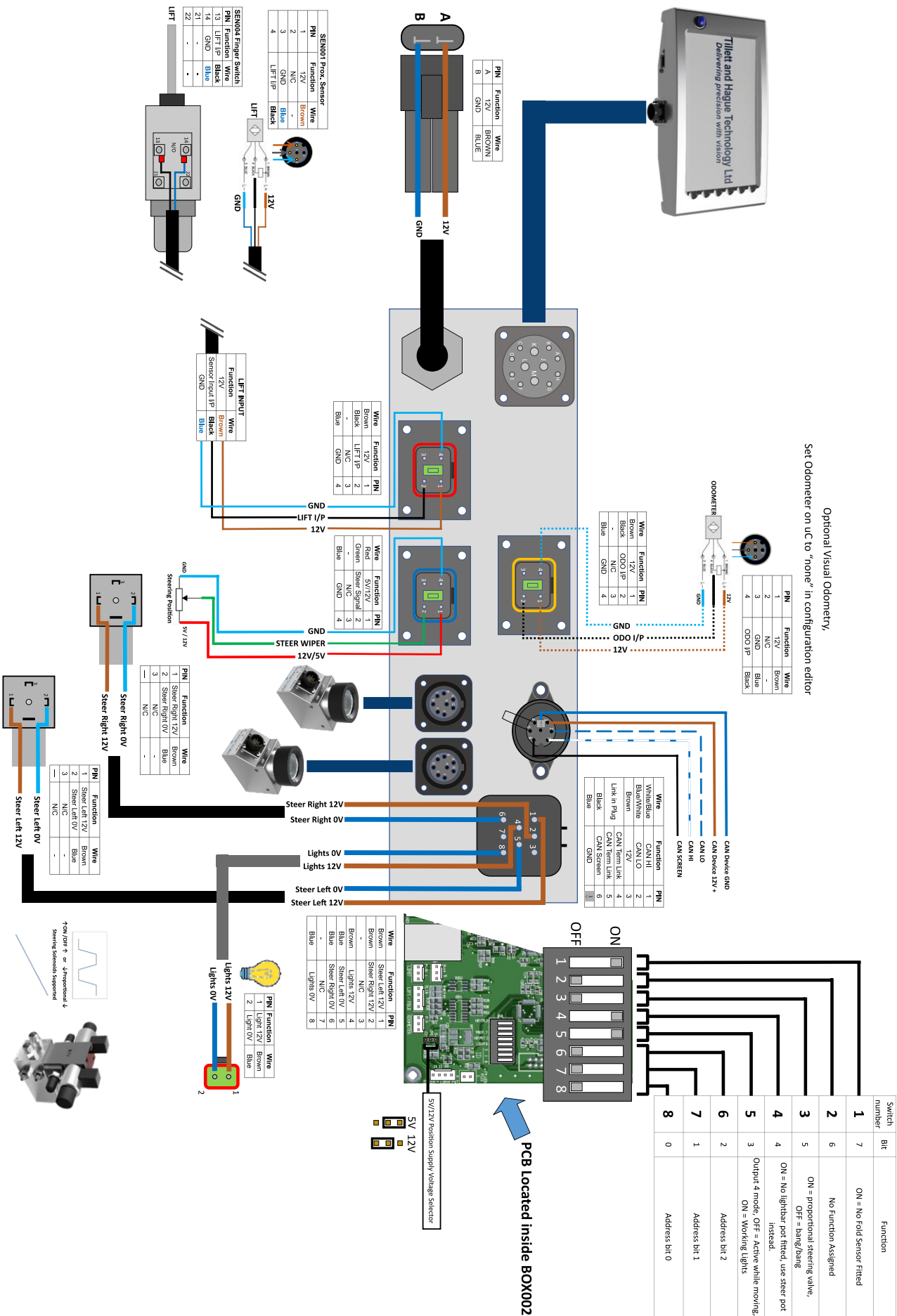
	Part Name	Part Function
1	Proportional control valve	Proportional directional control
2	Proportional solenoid coil	Activates valve to direct oil flow
3	Pressure Reducer adjuster and locking nut	Used to set operating pressure
4	Test point gauge	Used to measure operating pressure, (only required for setup and not routine running)

Hydraulic fault finding:

The advanced settings and diagnostics screen include a steering test which can be helpful in diagnosing hydraulic problems. If in doubt, run this simple test. It will interactively ask you which direction is left, and which is right, show if the hydraulic supply is connected the wrong way around or is believed to be inversed, if the flow rate is too high, or too low. The test also attempts to diagnose faulty position sensors by detecting irregular output signals, or a mechanical jam for which you get the message "Hit stop". The "Hit stop" message can also be triggered by hydraulic issues such as entrapped air, or low flow rates.

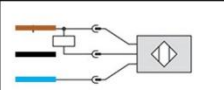


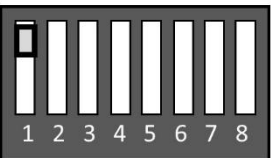
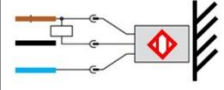
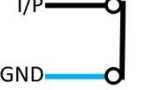


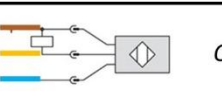


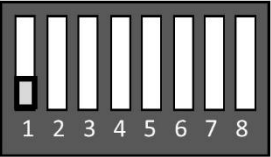
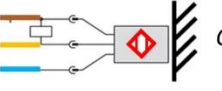


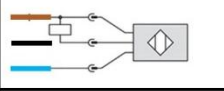
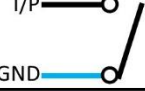
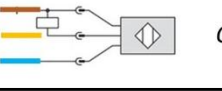


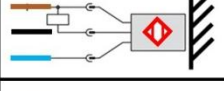
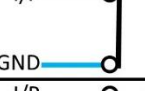
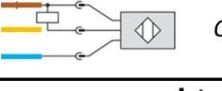


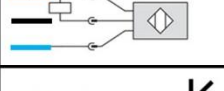

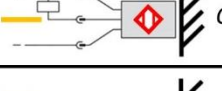


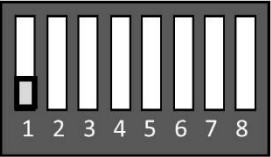
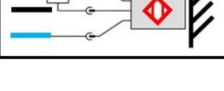
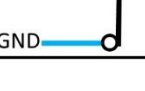
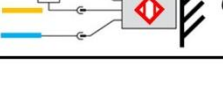
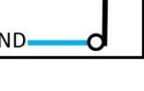

Single section schematic

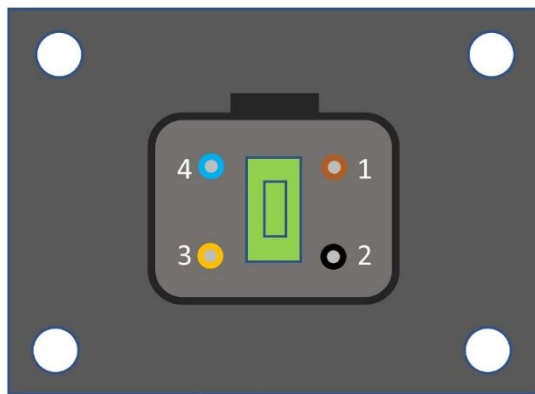
Schematics for multi-section systems are available on request.



Implement module Lift and Fold DIP switch settings table

This table lists all potential lift and fold input combinations and the effect they have on lift status. Connections for both NPN type proximity sensors and finger switches are shown. The DIP switch can be found on the microcontroller PCB inside the implement module (BOX002).

Mode	LIFT Channel	FOLD Channel	Lift Status	DIP Switch Settings
LIFT	 OR 	NOT USED		ON 
LIFT	 OR 	NOT USED		OFF 
FOLD	NOT CONNECTED	 OR 		
FOLD	NOT CONNECTED	 OR 		
LIFT+ FOLD	 OR 	 OR 		
LIFT+ FOLD	 OR 	 OR 		
LIFT+ FOLD	 OR 	 OR 		
LIFT+ FOLD	 OR 	 OR 		



BOX002	
PIN	Function
1	12V
2	Lift I/P
3	Fold I/P
4	GND